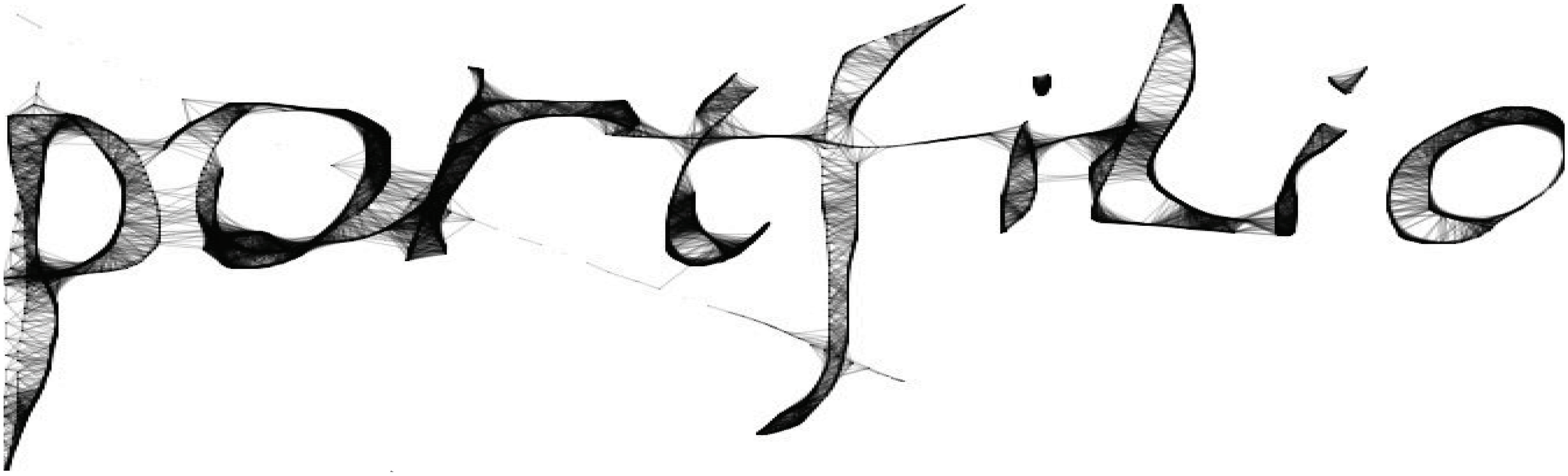


portfolio

JAIMME **GUAN**

CONTACT **ME**

YU GUAN
FLAT3, drummond street
NW1 2PB LONDON
+044 (0)7419214403
JAIMME6666@GMAIL.COM

DATE OF BIRTH: 6 JUNE 1983
NATIONALITY: CHINA

AWARDS & **EXHIBITION**

Bronze Ear Prize Winner of Bartlett in GAD
(individual , it usually for group work)
"1st Element" in London Kinetic Art Fair 2014

MY **EDUCATION**

2013.9-2014.9
BARTLETT SCHOOL OF ARCHITECTURE
MArch Graduate Architectural Design
Bronze Ear Prize Winner
Distinction
Design 94 (2nd of programme)
Reasearch thesis 95 (1st)
LONDON.UK

2012.9-2013.1
LABORATORY FOR COMPUTATIONAL DESIGN
Professional Study of Computational design
Researches on parametric design
of digital technology from Workshops
(Indexing ,Processing ,Interactive Media)
(held by Architectural Association China Club)
BEIJING, P.R.C.

2002.9-2007.9
WUHAN NATIONAL UNIVERSITY
Bachelor of Architecture
WUHAN, P.R.C.

Reference

Alisa Andrasek
Director, Graduate Architectural Design,
Bartlett School of Architecture
Biothing, founder and principal
Bloom Games, partner
London,UK
Tel: +44 7545338136
Email:andrasek@gmail.com

I am an Architect(5 years working experience) with strong coding capacity and enthusiasm of robotic and data interface. I am crazy about designing from bits to atoms, by programming, engineering, fabrication. I am an Architect but also like a creator which is half scientist and half artist. With the desire to create kinetic Architecture to observe more in the world, I am forever young. Since graduation of my bachelor degree in 2002, I have engaged in more than 20 different architecture projects , from concept design to detail design, including large-scale commercial centers and high rise buildings. After 2013, I went to LCD and Bartlett to seek new future of Architecture.

PROJECTS 2014 (Installation , Product & Robot)

"FLY FLUID" ....Interactive Installation"(concept, mechanism, software ,Charliy finish the fabrication)
"1ST ELEMENT".........The first 3 axises spherical robot in world. (coding , engineering, fabrication)
(Prototype 4 shown in UCL Quad) https://www.youtube.com/watch?v=yOC1OB90AOk
(Design and Animation) http://youtu.be/53RNcsAwLEk
(In Kinetic Art Fair 2014) http://youtu.be/TQ7BNy6ORIc
(After graduate from bartlett)
"VISION LIGHT" ....Kinetic intelligence light (coding ,mechanism design)
"SPACE DATA INTERFACE"...(concept)

RESEARCH

(During the study in Bartlett School , individual)
Morphology and HRI in Architectural Robotics: Interfering Proximity Behavior by Spherical Robots
(After graduate from bartlett , from September to now)
The omni-direction high speed spherical robot: cooperation of PID algorithm and FO control.

WORK **EXPERIENCE** & MAIN **PROJECTS**

SENIOR ARCHITECT (08.2011-09.2012)
ATKINS CONSULTANTS CO.LTD.
http://www.atkins.com.cn/mainland/default.htm
Fenglong 500m Super High Project Concepts Competition ....(concept design)
HangzhouTaihu Holiday Hotel..(shape-designing, and detail design)
Hainan Wenchang Holiday Resort.................................(participated in the whole process of design)

ARCHITECT & PROJECT MANAGER (11.2009-06.2012)
PUBLIC CONSTRUCTION DEPARTMENT
PEDDLE THORP MELBOURNE PTY.LTD. W
PEDDLE THORP(MELBOURNE)AISA
http://www.ptma.com.cn/
Guiyang China Railway Center Project....................................(Project manager & principle desinger)
Chengdu Logistics Center Project..............................(as the principle designer,organized my team)
Chong qing Hot spring Holiday Hotel ....(Project manager)
Bid for Shenzhen Bolun Vocational Skills School...............(makingprojectplananditsimplementation)
Bid for Super High Building for Opera...(group work ,successful bid)
Bid for Chongqing Bishan Middle & Elementary School..(concept design)
Guangzhou Bio-island Project..(principle designer)
Chongqing Xiushan Community and Holiday Hotel Project ....(principle designer)

ARCHITECT (2007.10 -2009.10)
ZHUBO DESIGN GROUP CO.LTD.
http://www.zhubo.com/
Dalian Xishan Zhengyuan Community Project......................(single design,plan to expansion design)
Bao li Changsha GreenSource Project..(single design)
Wanke An ping jie Residential Design...(elevationdesign)
Ma shan zhai Sport Project Design..(shapedesign)
Chongqing Da chuan Kindergarten Design..(concept to detaildesign)

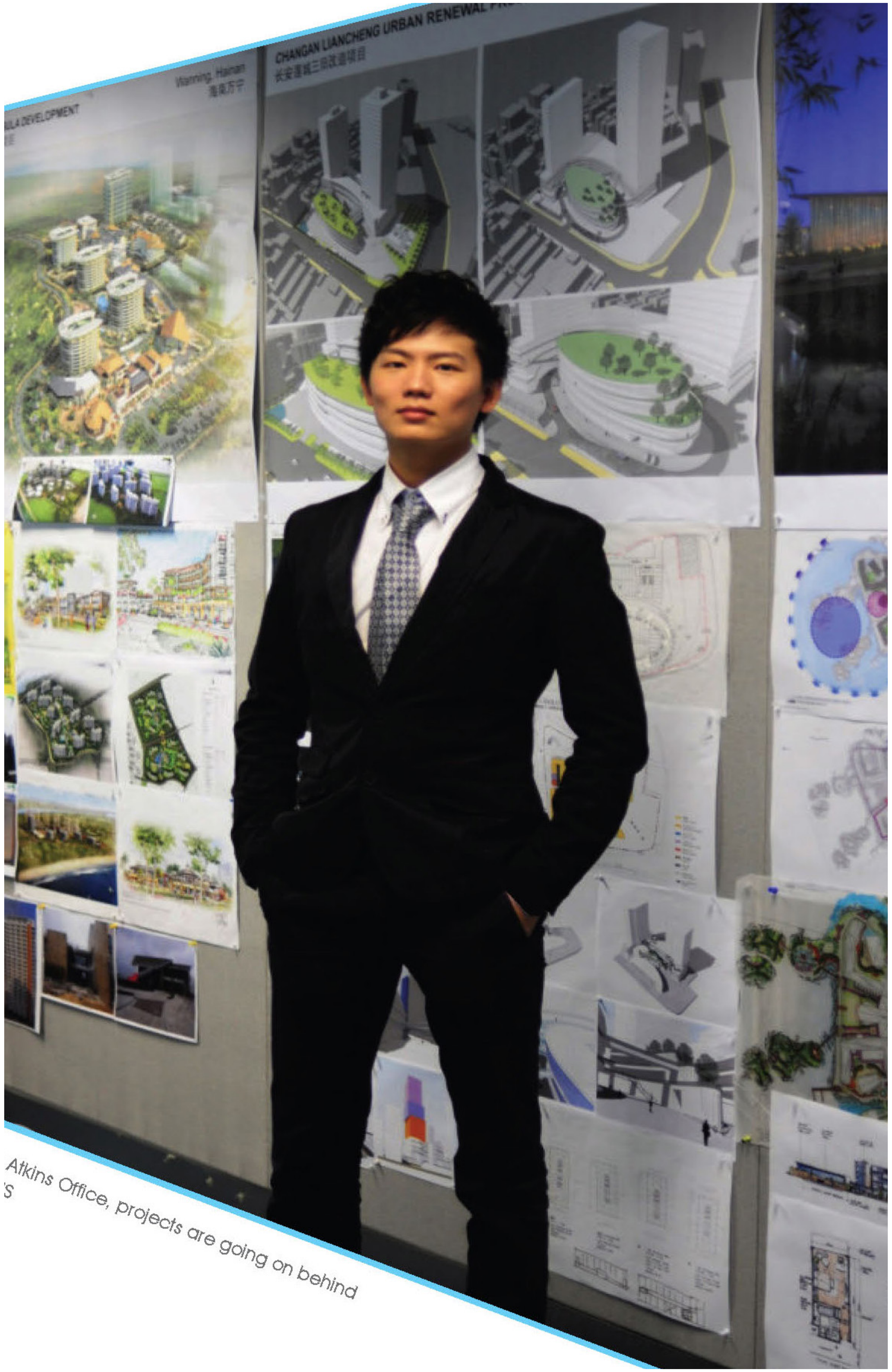
SKILL **SET**

PROGRAM	
Adruino	●●●●
Processing	●●●●
Firefly	●●●●
C++	●●●
Java	●●
Basic	●●●●
Pasica	●●
Logo	●●●
Python	●●

MODELING & VISION	
Auto CAD	●●●●
3D MAX	●●●
Rhino	●●●●
Maya	●●
Keyshot	●●●●
Zbrush	●●●
Adobe Photoshop	●●●●
Adobe Indesign	●●●●
Adobe Premier	●●●

HARDWARE	
Adruino Board	●●●●●
Wireless Control Device	●●●●
Servos and Step Motors	●●●●●

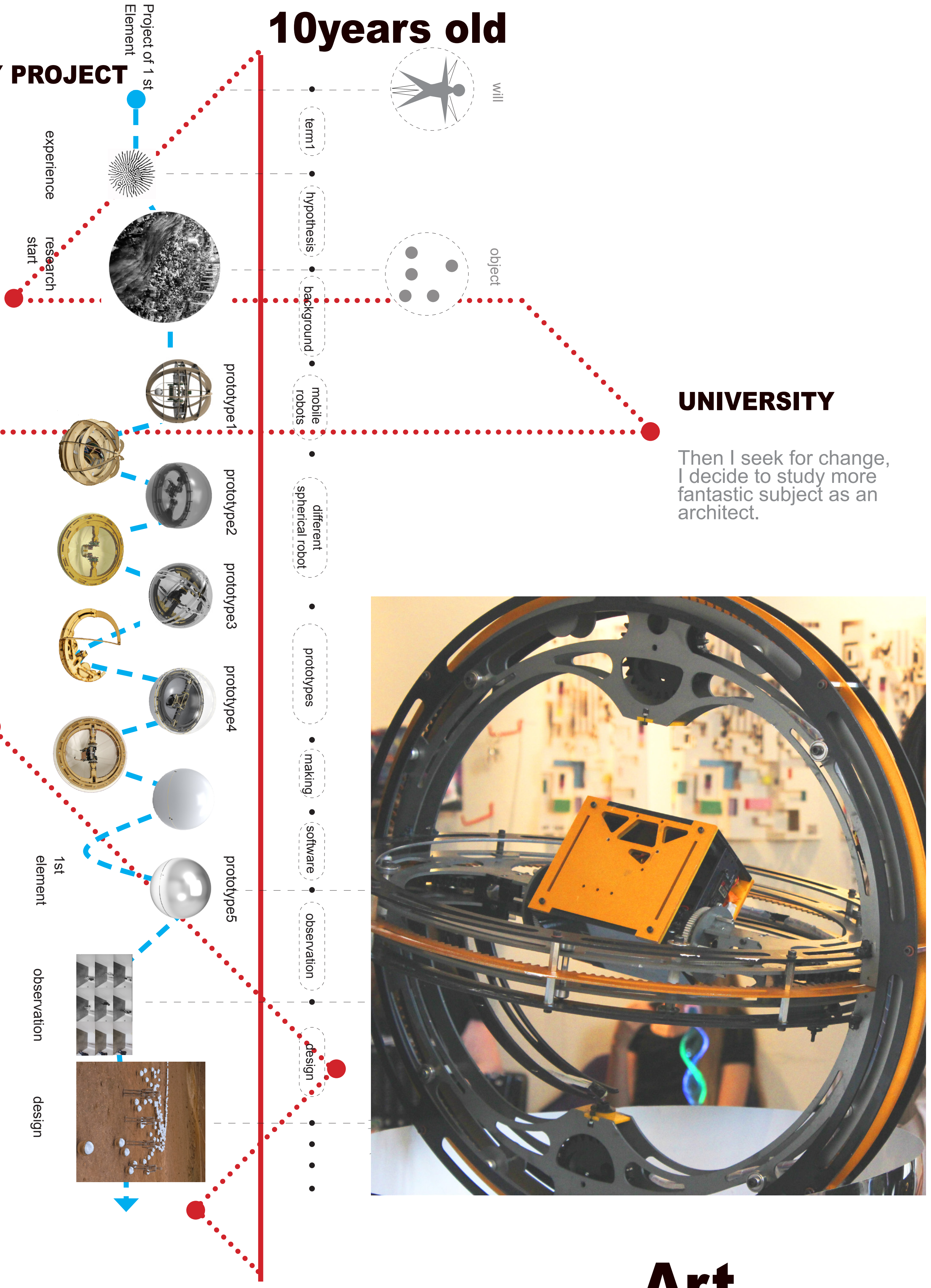
FABRICATION
CNC Machine
Water Jet
3D Printer
ABS Robot
Universal Robot



'S
Atkins Office, projects are going on behind

My Education is a blend of Science and Art

10years old



MY PROJECT

ELEMENT& HIGH **SCHOOL**

when I was 12 years old , I already obtain three different program languages . Silver medal winner of youth coding competition in my country. Before I went to university , I was a totally “GEEK”.

UNIVERSITY

Then I seek for change, I decide to study more fantastic subject as an architect.

LCD

Study computational design and do experiments.

BARTLETT **SCHOOL**

I created spherical robot in GAD .

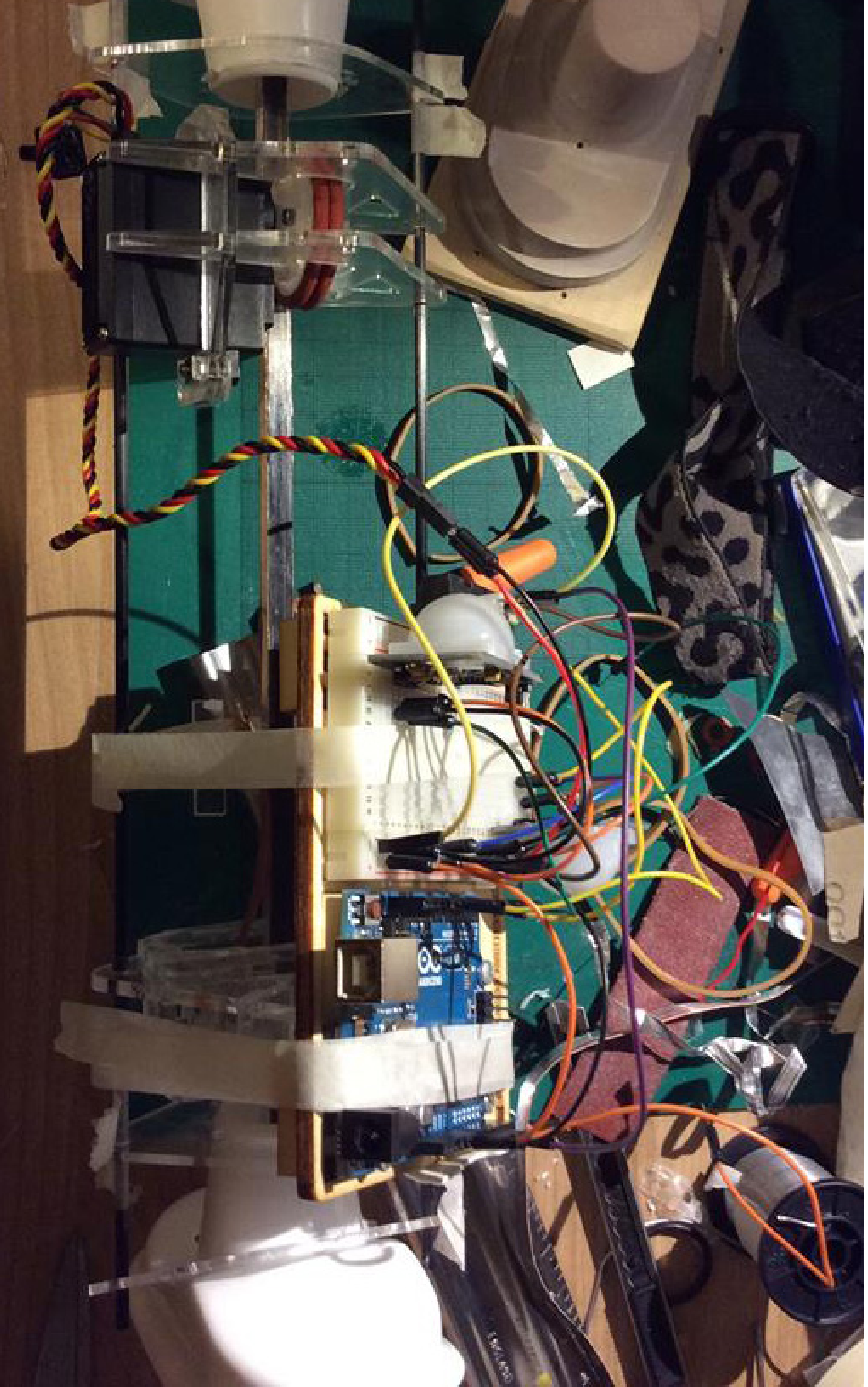
Science

Art

31 years old

Programming and Hardware

Debug in 4 am main libruary of UCL

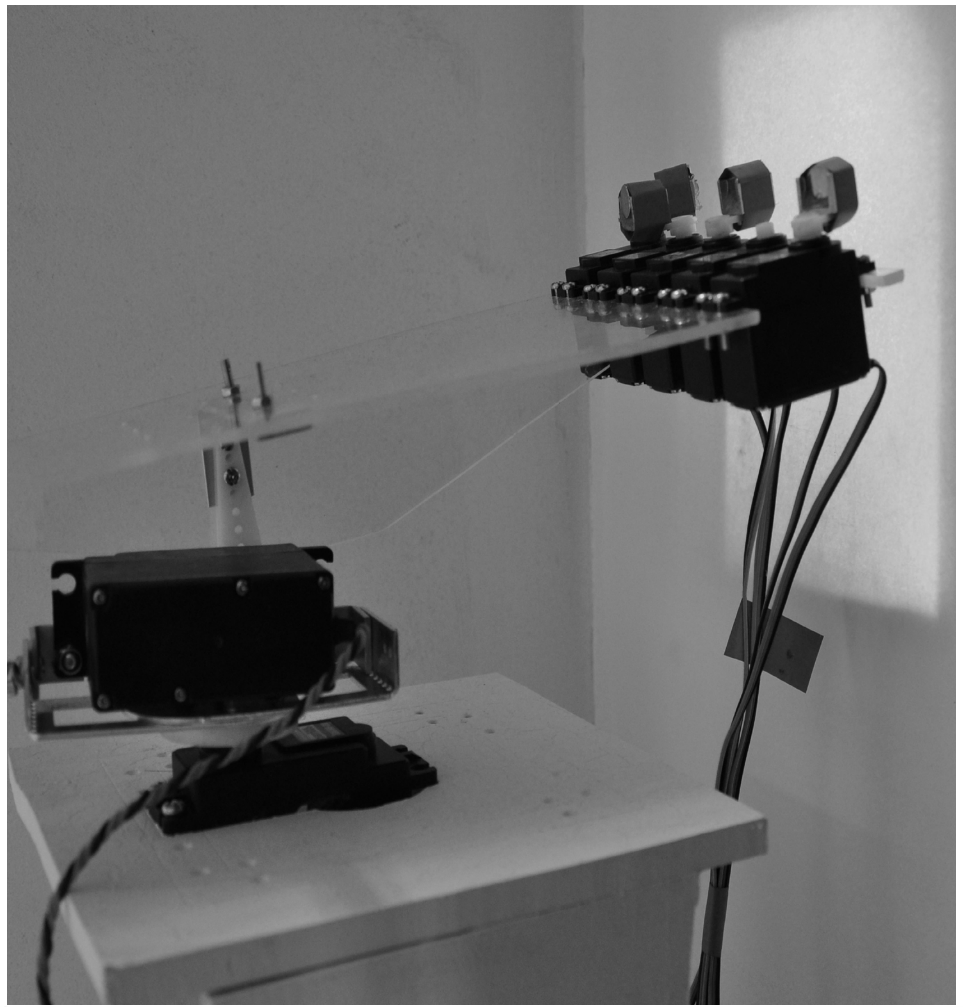


```
long previousMillis = 0;
long interval = 20;
int pulseTimeMID = 1450;
int pulseTime = 1650;
int servoPinA = 11;
int calibrationTime = 1;
int led1=0;
int led2 =0;
int led3 =0;
int  fadeValue1;
int  fadeValue2;
int  fadeValue3;
//the time when the sensor outputs a low impulse
long unsigned int lowIn1;
long unsigned int lowIn2;

//the amount of milliseconds the sensor has to be low
//before we assume all motion has stopped
long unsigned int pause = 5;

boolean lockLow = true;
boolean takeLowTime;
boolean lockLow1 = true;
boolean takeLowTime1;
boolean h1=true;
boolean h2=true;
int pirPin = 3;    //the digital pin connected to the
PIR sensor's output
int pirPin1 = 6;
int ledPin1= 9;
int ledPin2= 10;
int ledPin3= 5;
int s=0;
int fuc=1;
int i=0;
int s1=0;
int fuc1=1;
int i1=0;

int RUNtime=1;
int StayTime=20000;

int sensorpin = 0;
int sensorpin1 = 1;    // analog pin used to connect
the sharp sensor
int val = 0;
int val1 = 1;   // variable to store the values from

long previousMillis = 0;
int val = 0;
int val1 = 1;   // variable to store the values from
sensor(initially zero)




void setup()
{
  pinMode(pirPin, INPUT);
    pinMode(pirPin1, INPUT);
  pinMode(ledPin1, OUTPUT);
    pinMode(ledPin2, OUTPUT);
  digitalWrite(pirPin, LOW);
   digitalWrite(pirPin1, LOW);
 Serial.begin(9600);       // Debugging only
  //give the sensor some time to calibrate
  Serial.print("calibrating sensor ");
//    for(int i = 0; i < calibrationTime; i++){
//      Serial.print(".");
//      delay(1000);
//      }
    Serial.println(" done");
    Serial.println("SENSOR ACTIVE");
    delay(50);

 // put your setup code here, to run once:
 pinMode(servoPinA, OUTPUT);
```

```
void loop()
  //////////////////distance
int a=  servospeed( pirPin1,h1,lockLow1 ,1550, lowIn1);
int b=  servospeed( pirPin,h2, lockLow ,1250 , lowIn2);
//int b=1450;
if (a==1550 && b== 1250){
pulseTime=1300;
}

if (a==1550 && b== 1450){
pulseTime=1400;
}
if (a==1450 && b== 1250){
pulseTime=1200;
}
if (a==1450 && b== 1450){
pulseTime=1300;
}

/////////////////////////////////////LED1
 // fade in from min to max in increments of 5 points:
  if ( led1==0) {
   for(int fadeValue1 = 0 ; fadeValue1 <= 255; fadeValue1
+=5) {
    // sets the value (range from 0 to 255):
    analogWrite(ledPin1, fadeValue1);

    // wait for 30 milliseconds to see the dimming effect
    delay(30);
  }
  led1=1;
  fadeValue1 = 255;
  }
if ( led1==2){
  // fade out from max to min in increments of 5 points:
   for(int fadeValue1 = 255 ; fadeValue1 >= 0; fadeValue1
-=5) {
    // sets the value (range from 0 to 255):
    analogWrite(ledPin1, fadeValue1);
    // wait for 30 milliseconds to see the dimming effect
    delay(30);

  }
  led1=1;
  fadeValue1 = 0;
}

if ( led1==1){
  analogWrite(ledPin1, fadeValue1);
}

Serial.println(fadeValue1);

///////////////////////////////////////////////////////
lED2
  if ( led2==0) {
   for(int fadeValue2 = 0 ; fadeValue2 <= 255; fadeValue2
+=5) {
    // sets the value (range from 0 to 255):
    analogWrite(ledPin2, fadeValue2);

    // wait for 30 milliseconds to see the dimming effect
    delay(30);
  }
   led2=1;
  fadeValue2 = 255;
  }
if (led2==2){
  // fade out from max to min in increments of 5 points:
   for(int fadeValue2 = 255 ; fadeValue2 >= 0; fadeValue2
-=5) {
    // sets the value (range from 0 to 255):
    analogWrite(ledPin2, fadeValue2);
    // wait for 30 milliseconds to see the dimming effect
    delay(30);

  }
  led2=1;
  fadeValue2 = 0;
}

if (led2==1){
  analogWrite(ledPin2, fadeValue2);
}
Serial.println(fadeValue2);


//////////////////////////////////////

///////////////////////////////////////////////////////
lED3
  if ( led3==0) {
   for(int fadeValue3 = 0 ; fadeValue3 <= 255; fadeValue3
+=5) {
    // sets the value (range from 0 to 255):
    analogWrite(ledPin3, fadeValue3);

    // wait for 30 milliseconds to see the dimming effect
    delay(30);
  }
   led3=1;
  fadeValue3 = 255;
  }
if (led2==3){
  // fade out from max to min in increments of 5 points:
```

```
int servospeed( int x,boolean h, boolean y,int z ,long unsigned int q){
  int result;

////////////////////////pir
      if(digitalRead(x) == HIGH){
        //digitalWrite(ledPin, HIGH);
               pulseTime=z;

         //Serial.print("HIGH ");   //the led visualizes the sensors
output pin state, and the led is broken , why I write this.
        if(y){
          // wait for  LOW before any further output is made: terrible
libruary i wanna make,,,damed .
          y = false;
          Serial.println("---");
         Serial.print("motion detected at ");
          Serial.print(millis()/1000);
         Serial.println(" sec");
          //delay(50);
          }
          h = true;
        }



//////////////////////////////////PIR

      if(digitalRead(x) == LOW){        pulseTime=1450;
        // digitalWrite(ledPin, LOW);  //the led visualizes // Serial.
print("LOW");
        if(takeLowTime){
         q = millis();          //save the time of the transition from
high to LOW
         h = false;       //done at the start of a LOW phase
         }
        //if the sensor is low for more than the given pause,
        //we assume that no more motion is going to happen
        if(!y && millis() - q > pause){
              //makes sure this block of code is only executed again
after
            //a new motion sequence has been detected
            y = true;
               Serial.print("motion ended at ");        //output your
behavior my son.
            Serial.print((millis() - pause)/1000);
            Serial.println(" sec");
             pulseTime=1450;
           // delay(10);
            }

        }
        result= pulseTime;
        return result;
```

Grasshopper to firefly to adruino to processing to java to internet in 1st term



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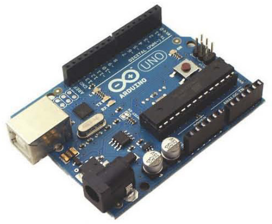
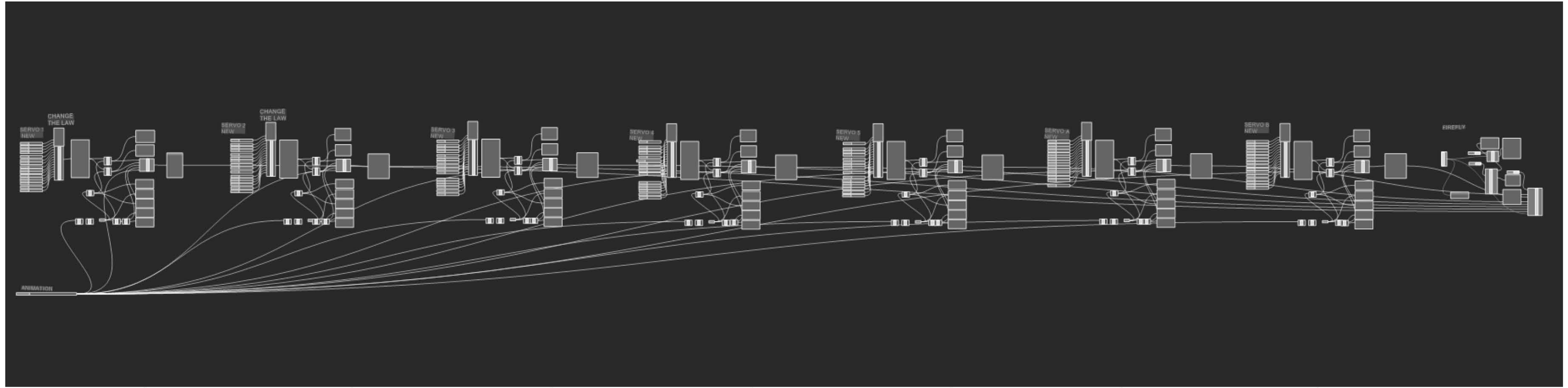
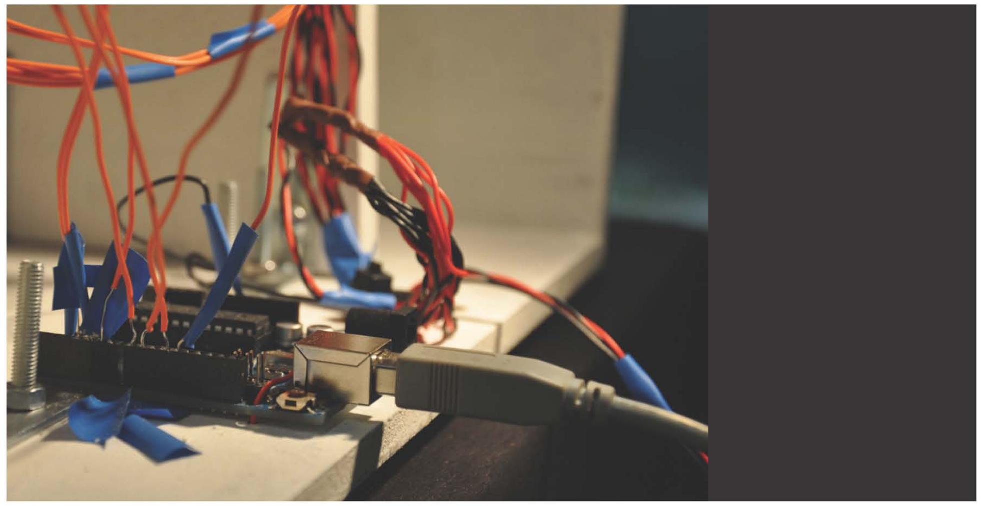
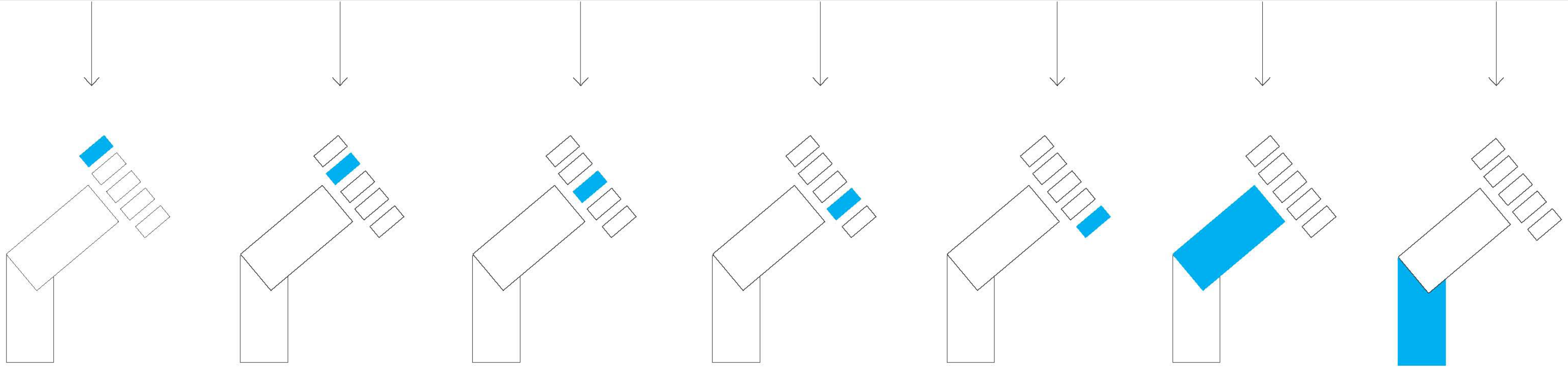


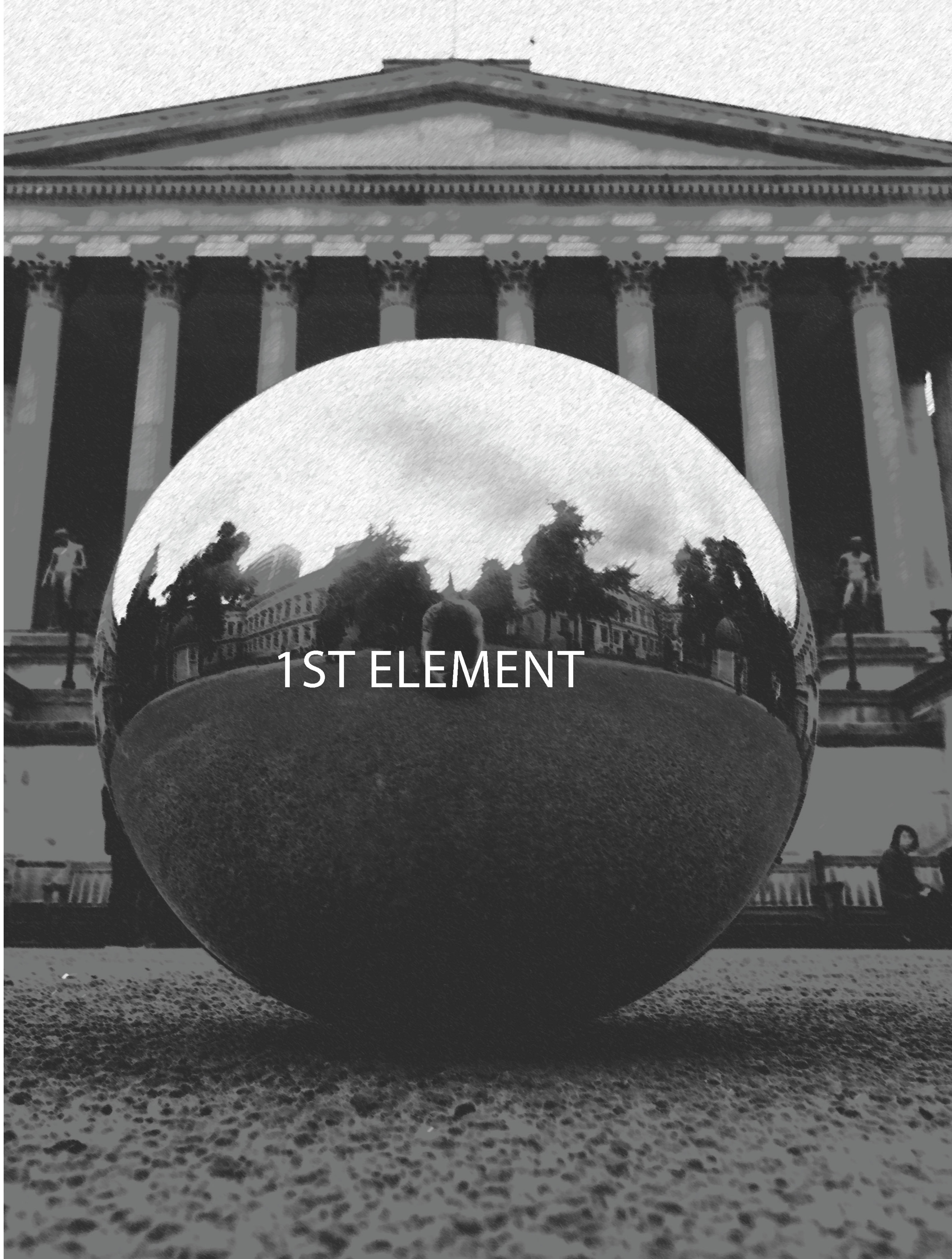




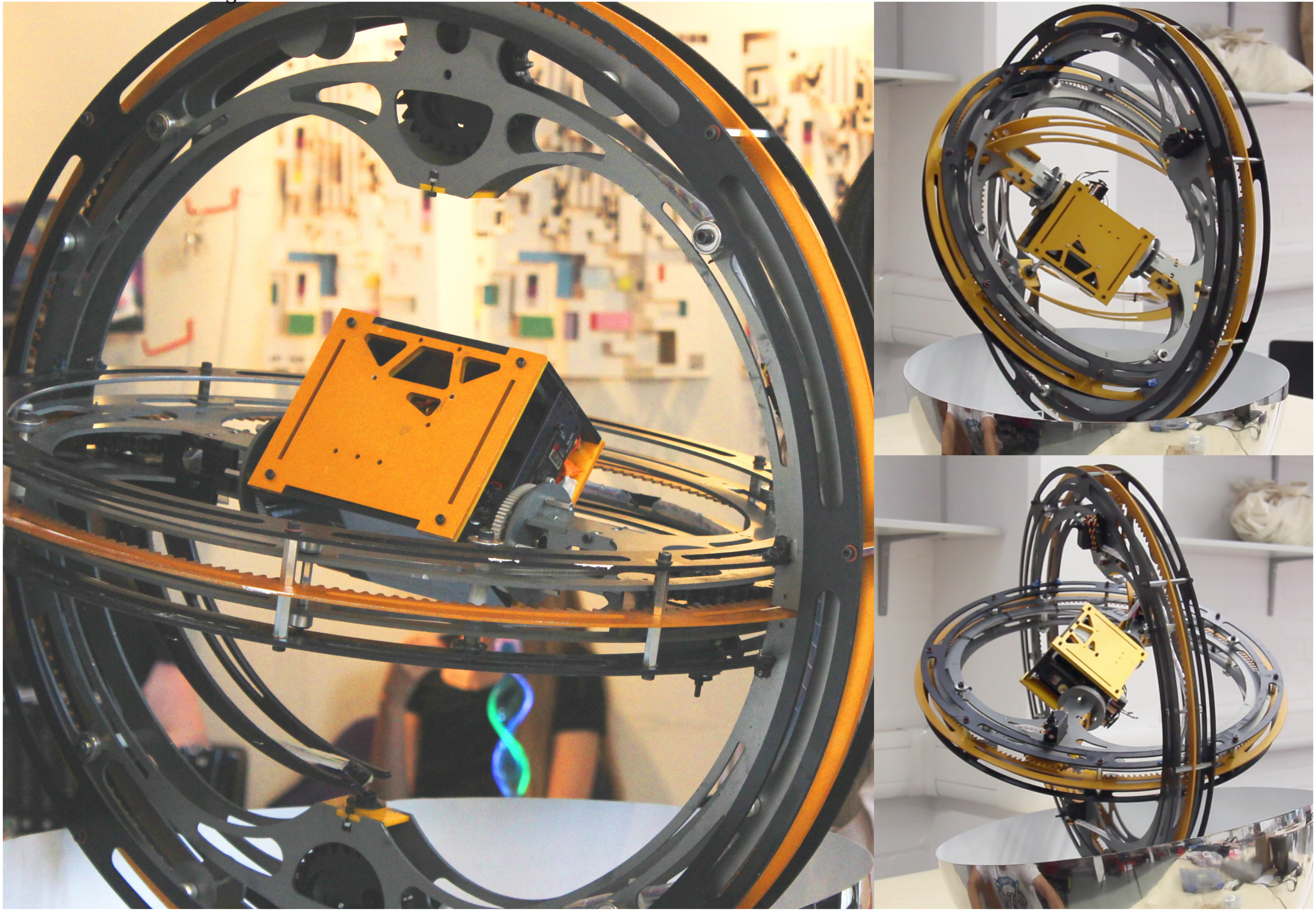


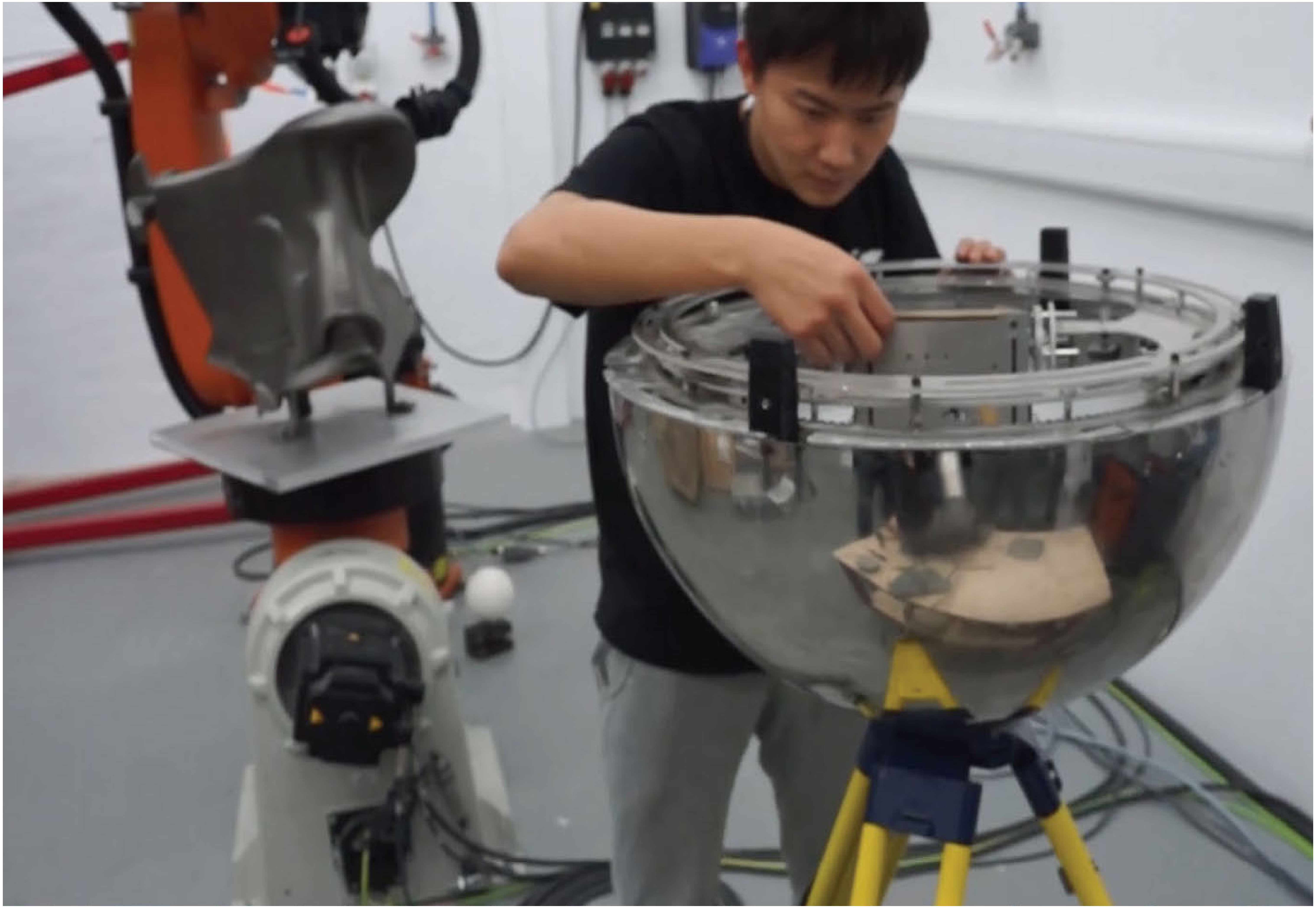
Robot & kinetic Architecture

“1st Element ” Project

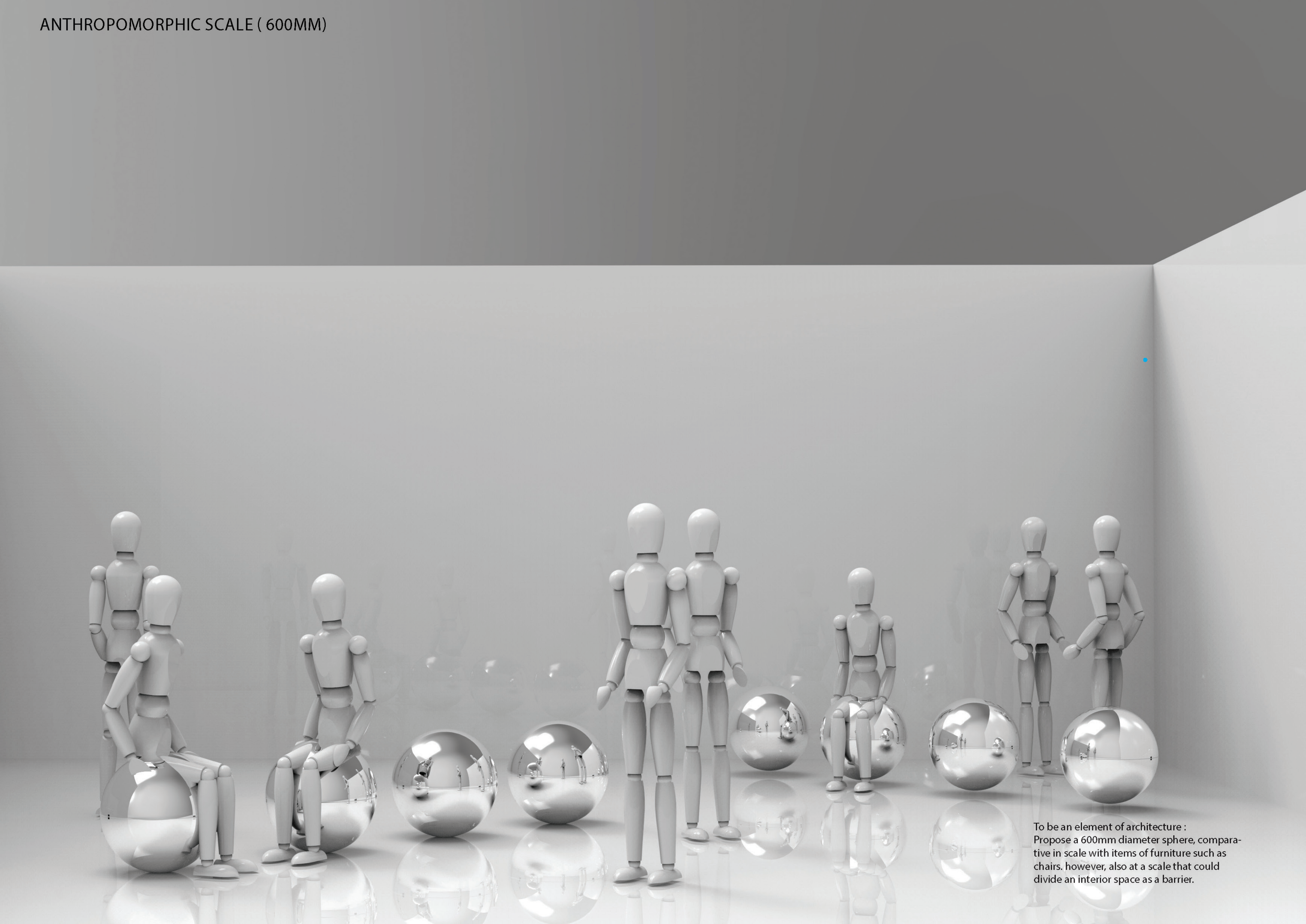


“1st Element” showing in Kinetic Art Fair 2014 London.



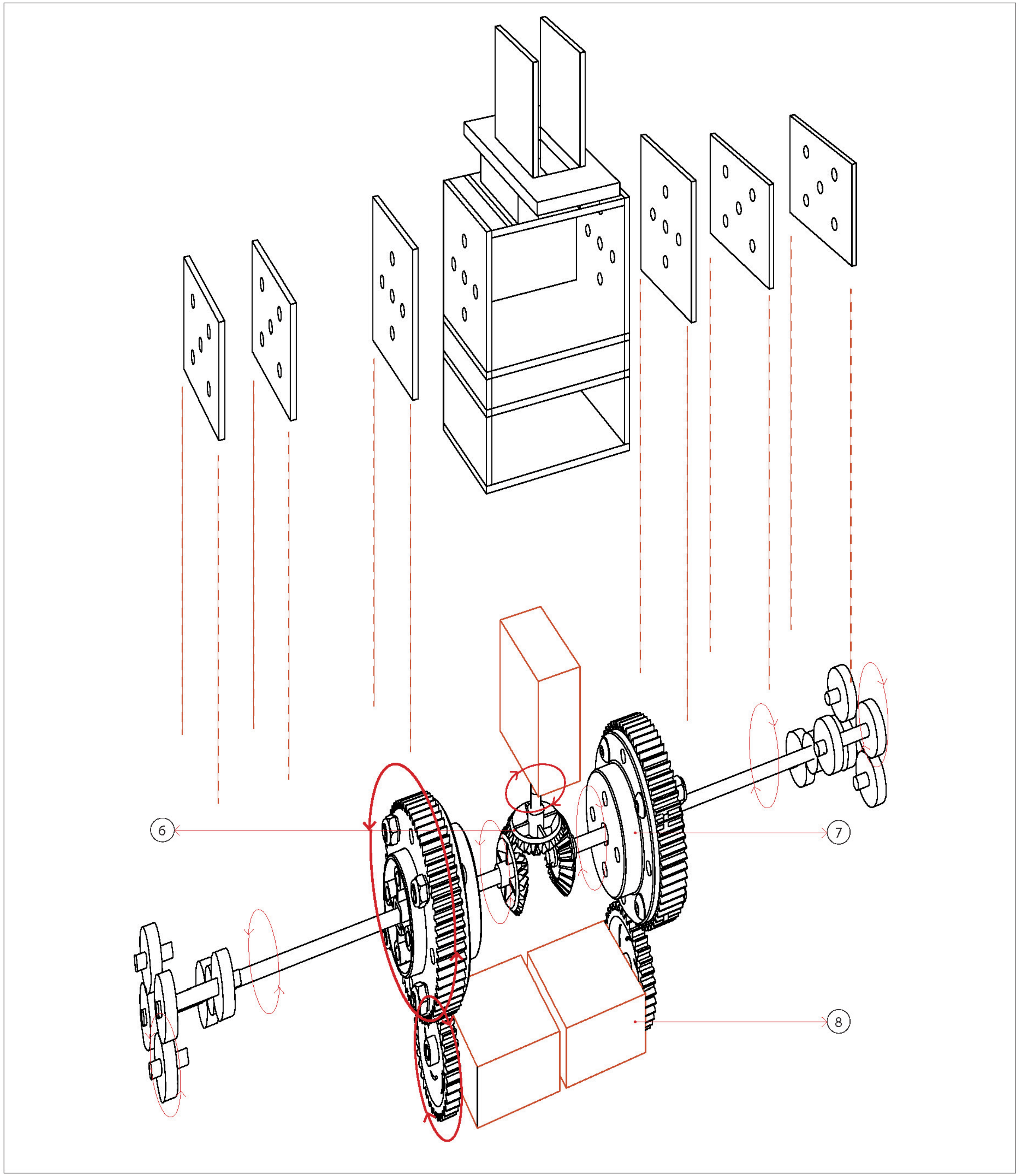


ANTHROPOMORPHIC SCALE (600MM)

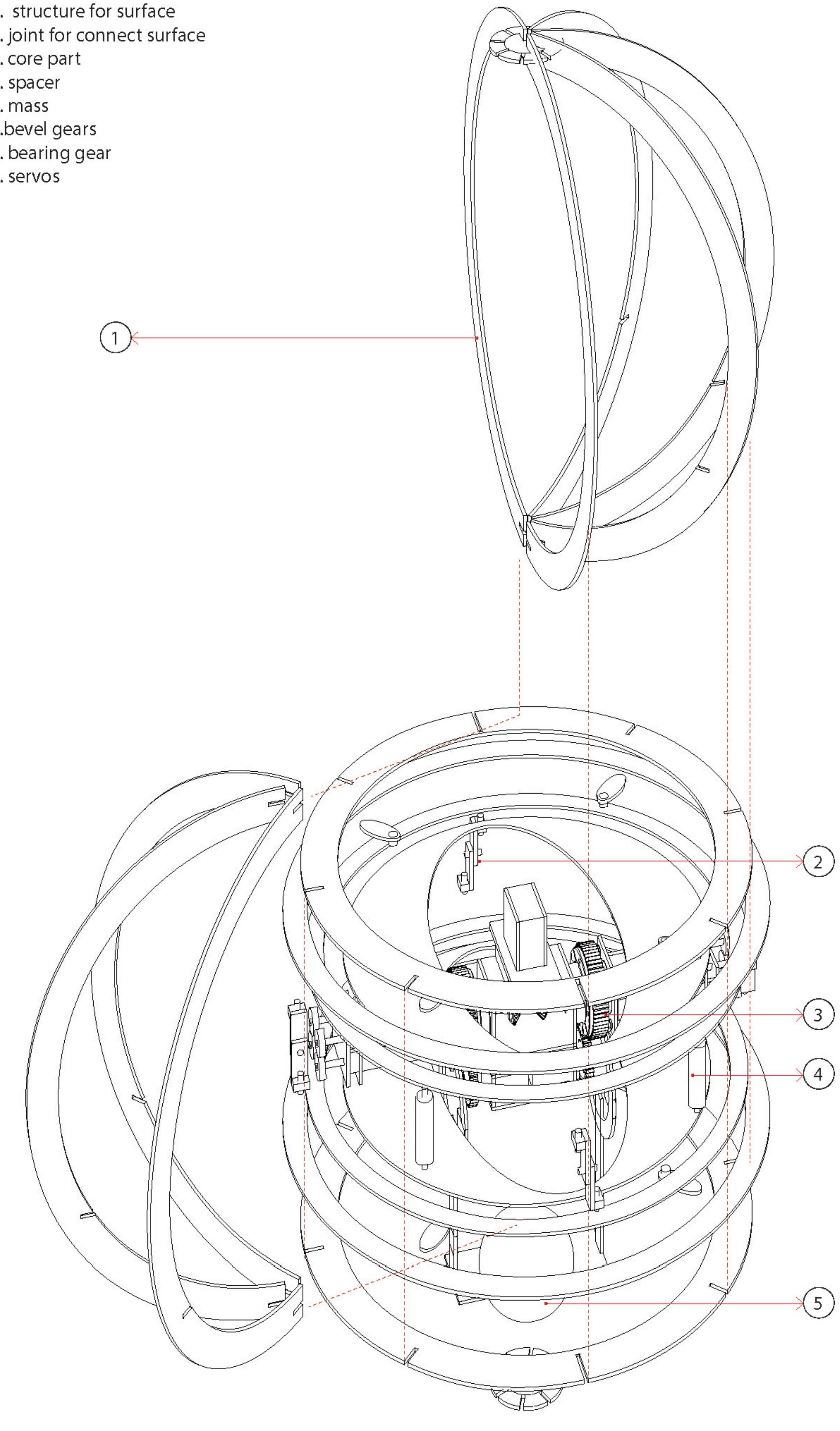


To be an element of architecture :
Propose a 600mm diameter sphere, comparative in scale with items of furniture such as chairs. however, also at a scale that could divide an interior space as a barrier.

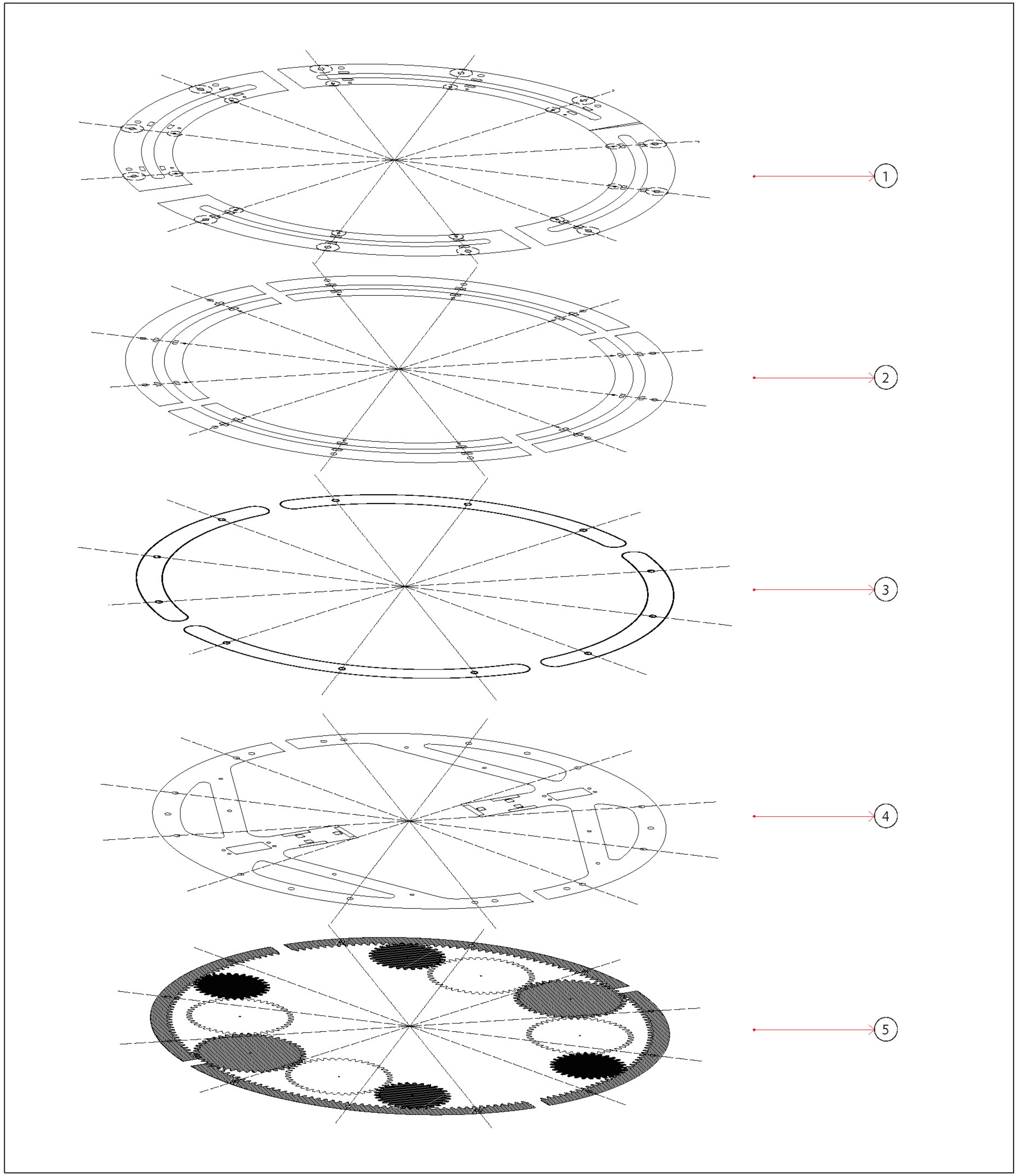
MECHANISM OF PROTOTYPE 1

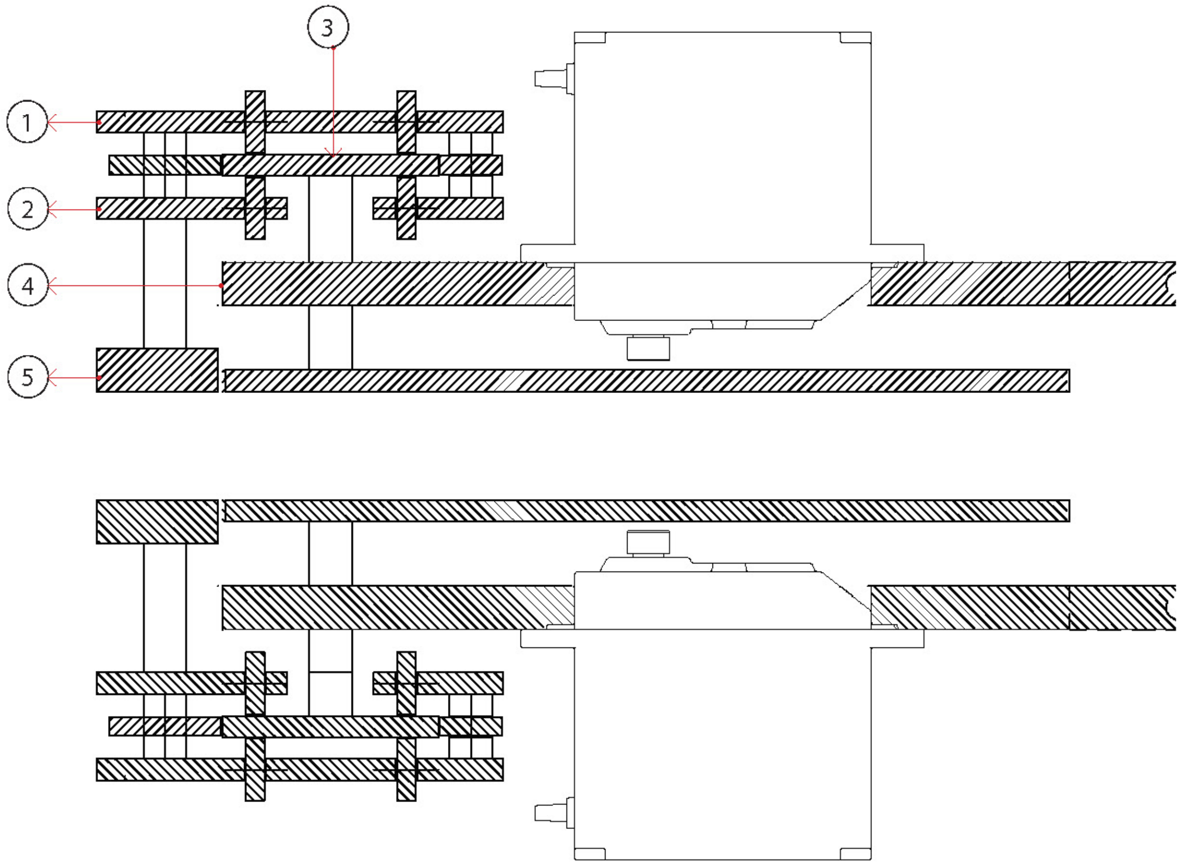


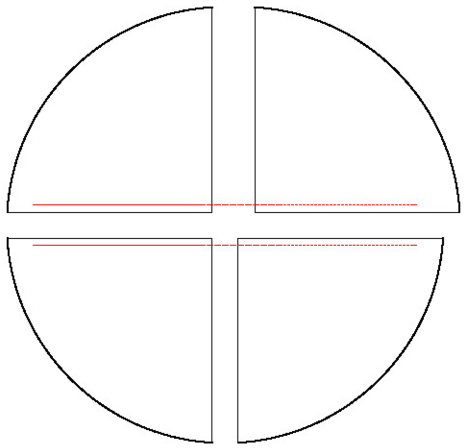
1. structure for surface
2. joint for connect surface
3. core part
4. spacer
5. mass
6. bevel gears
7. bearing gear
8. servos



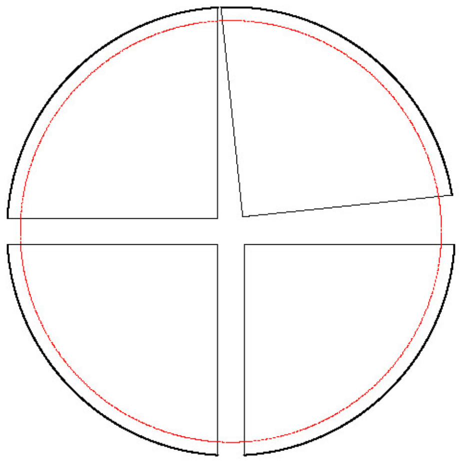
MECHANISM OF PROTOTYPE 2







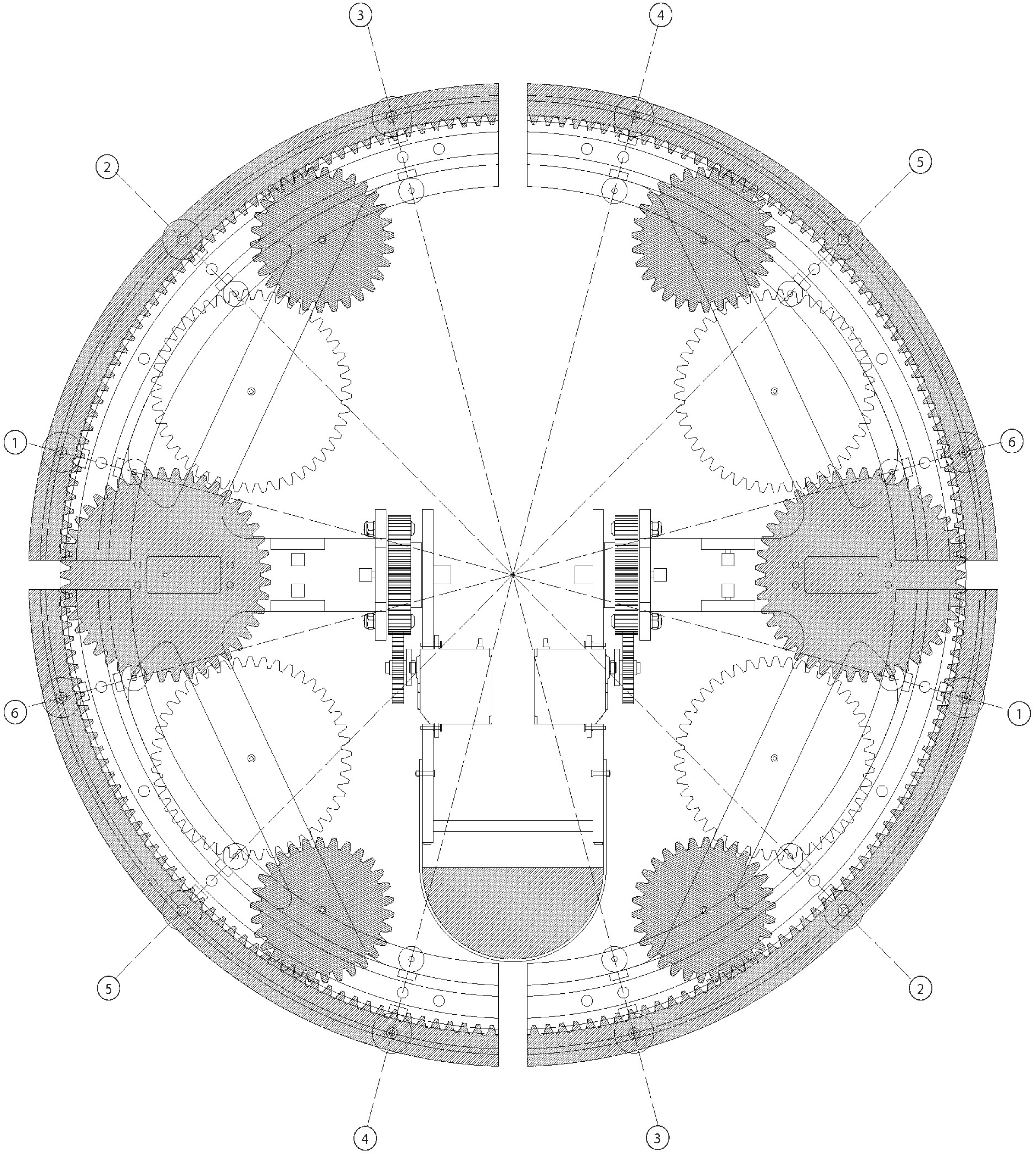
section , departure

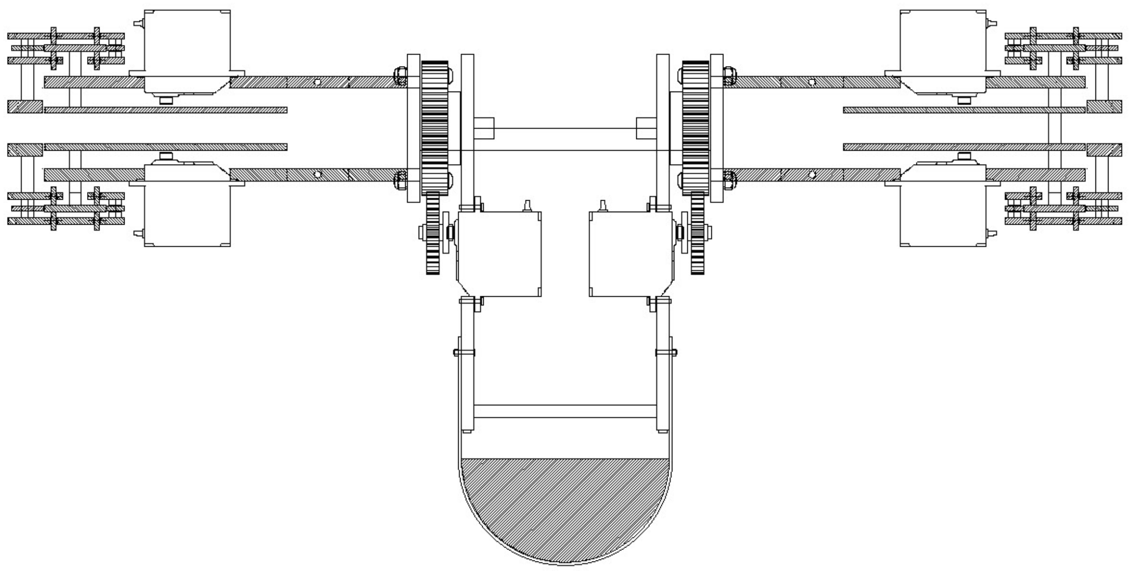


plan, collision

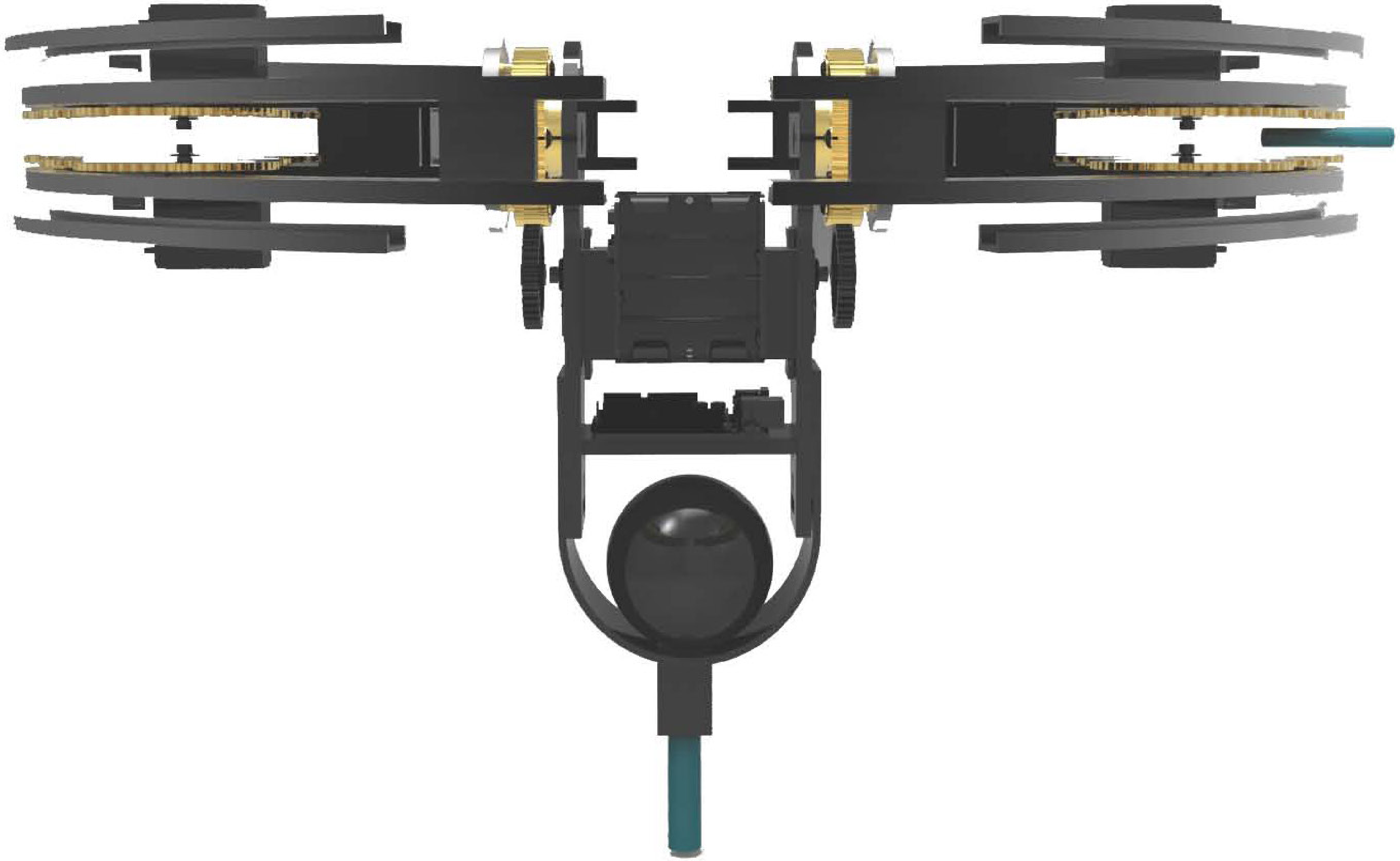
1. plan 1, bearing layer
2. plan 2
3. plan 3
4. plan 4 , servo layer
5. plan 5, gears layer

POTENTIAL MECHANISM TO BREAK THE SPHERE

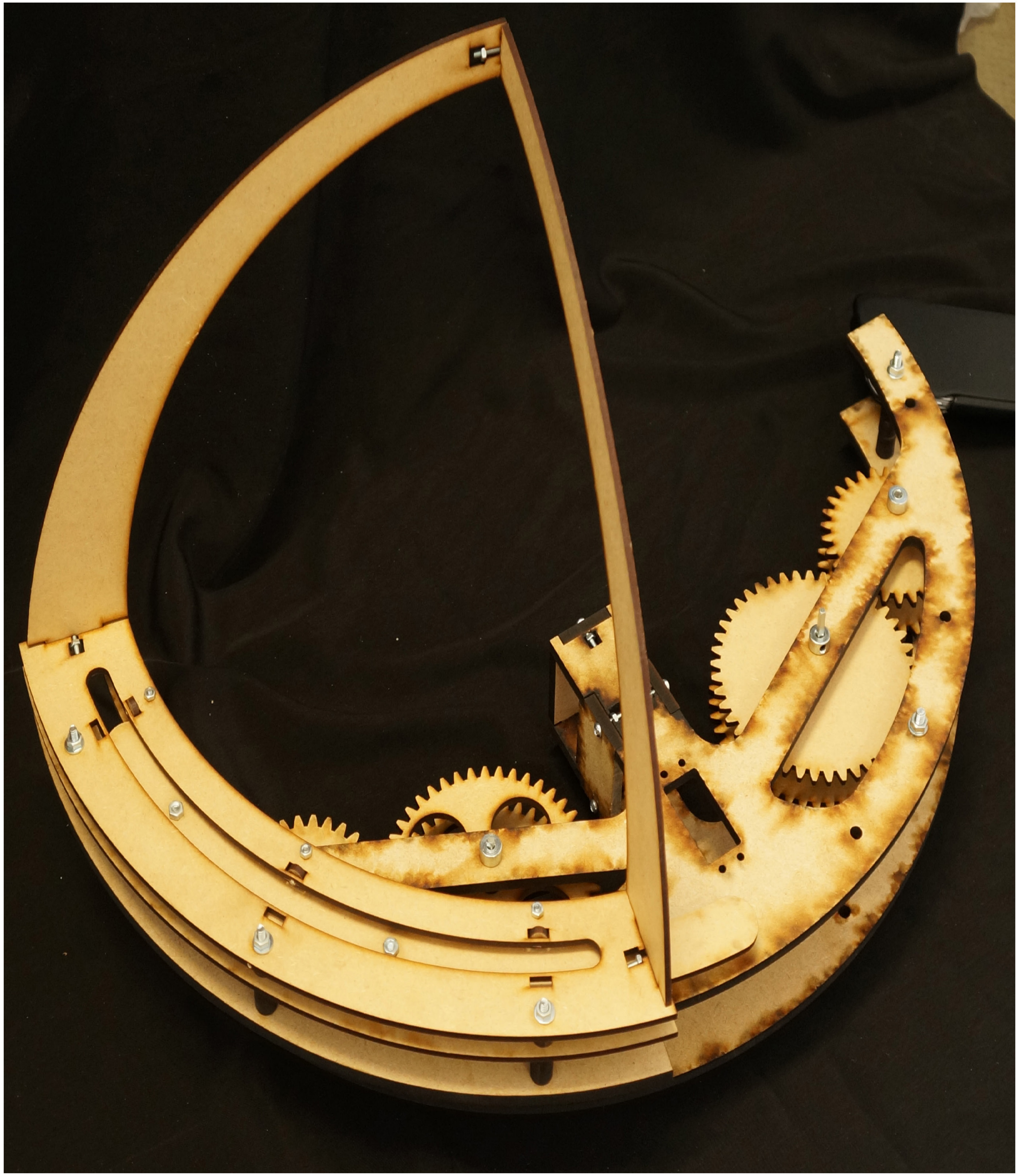


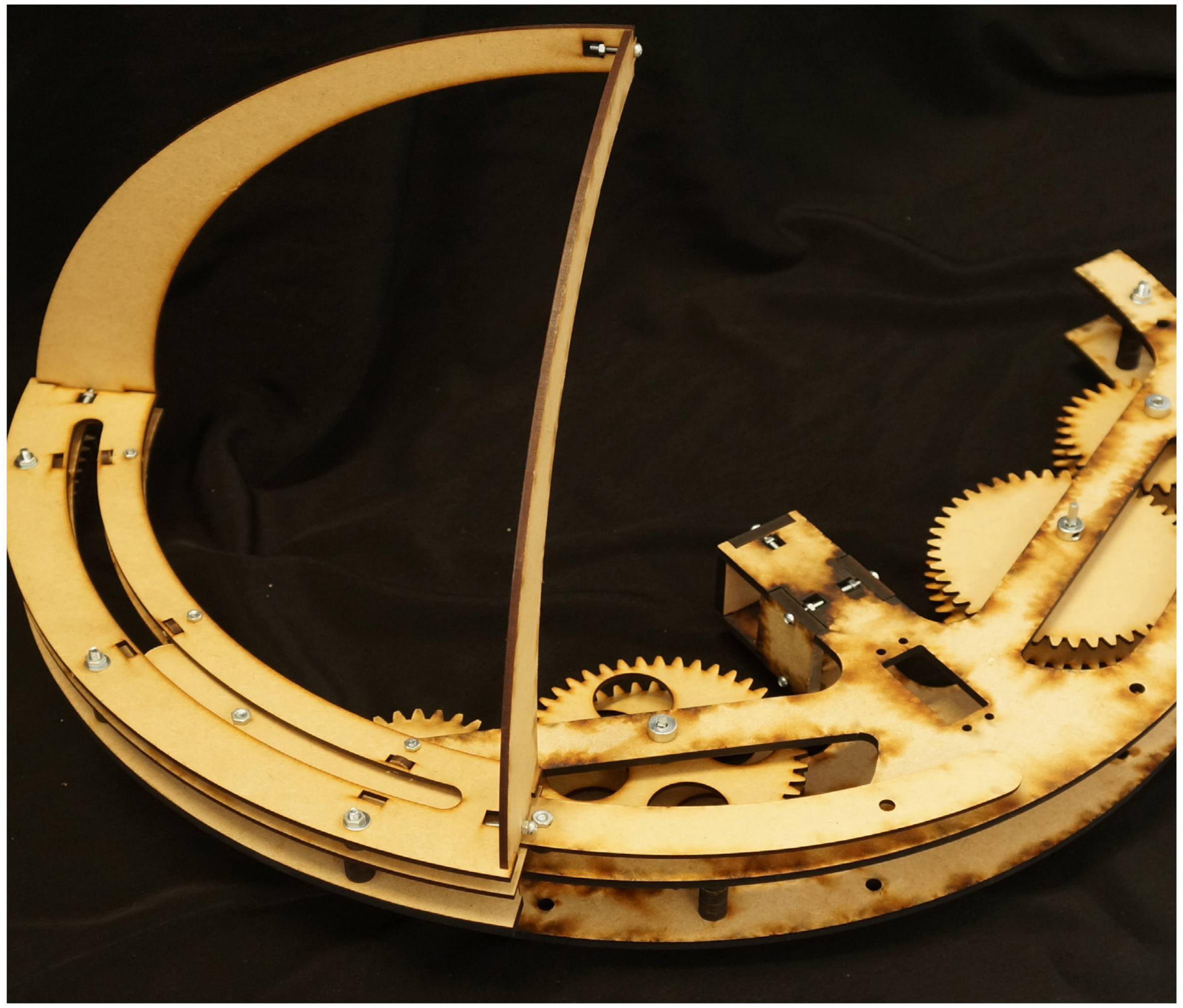


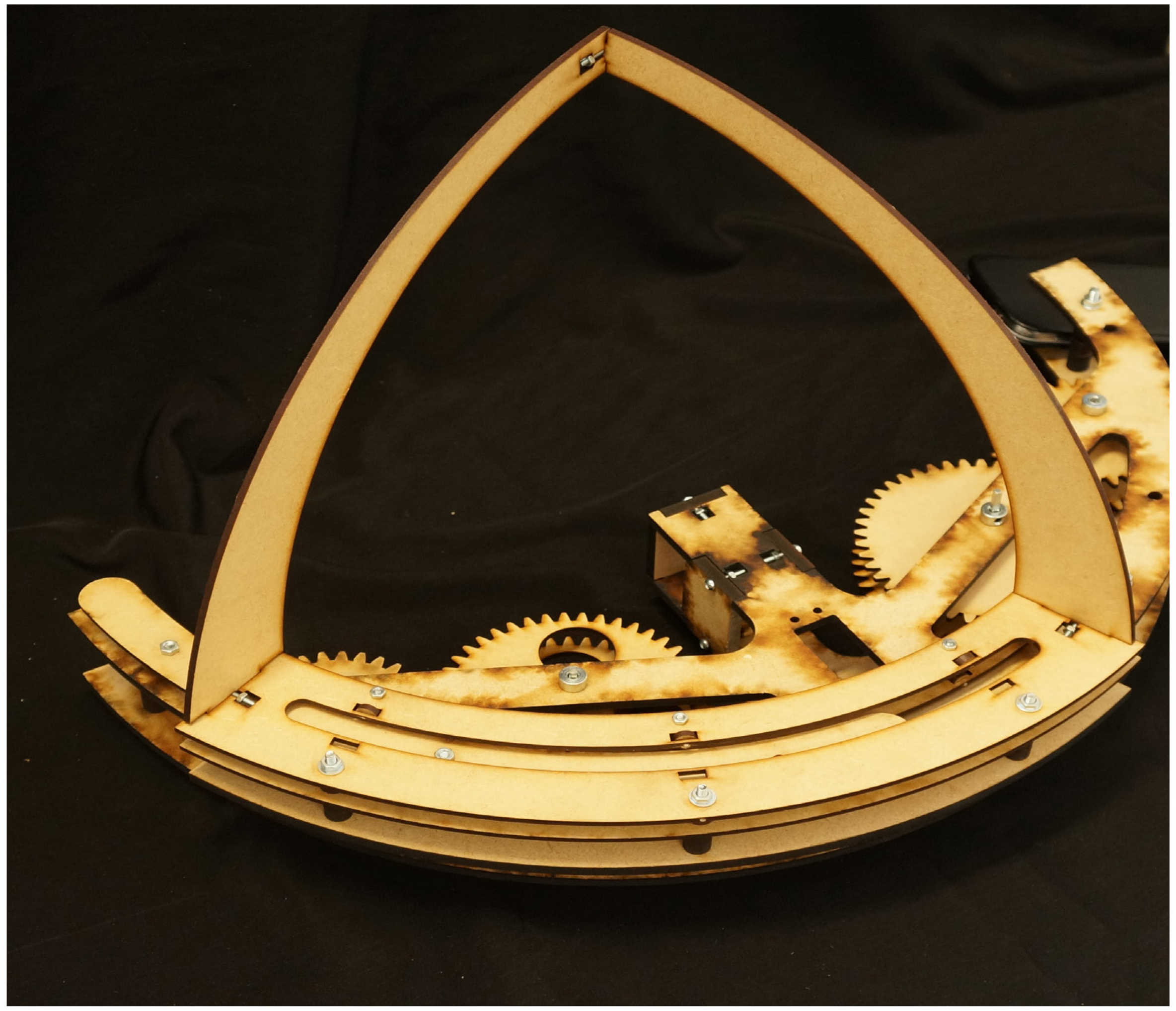
1. plan
2. section

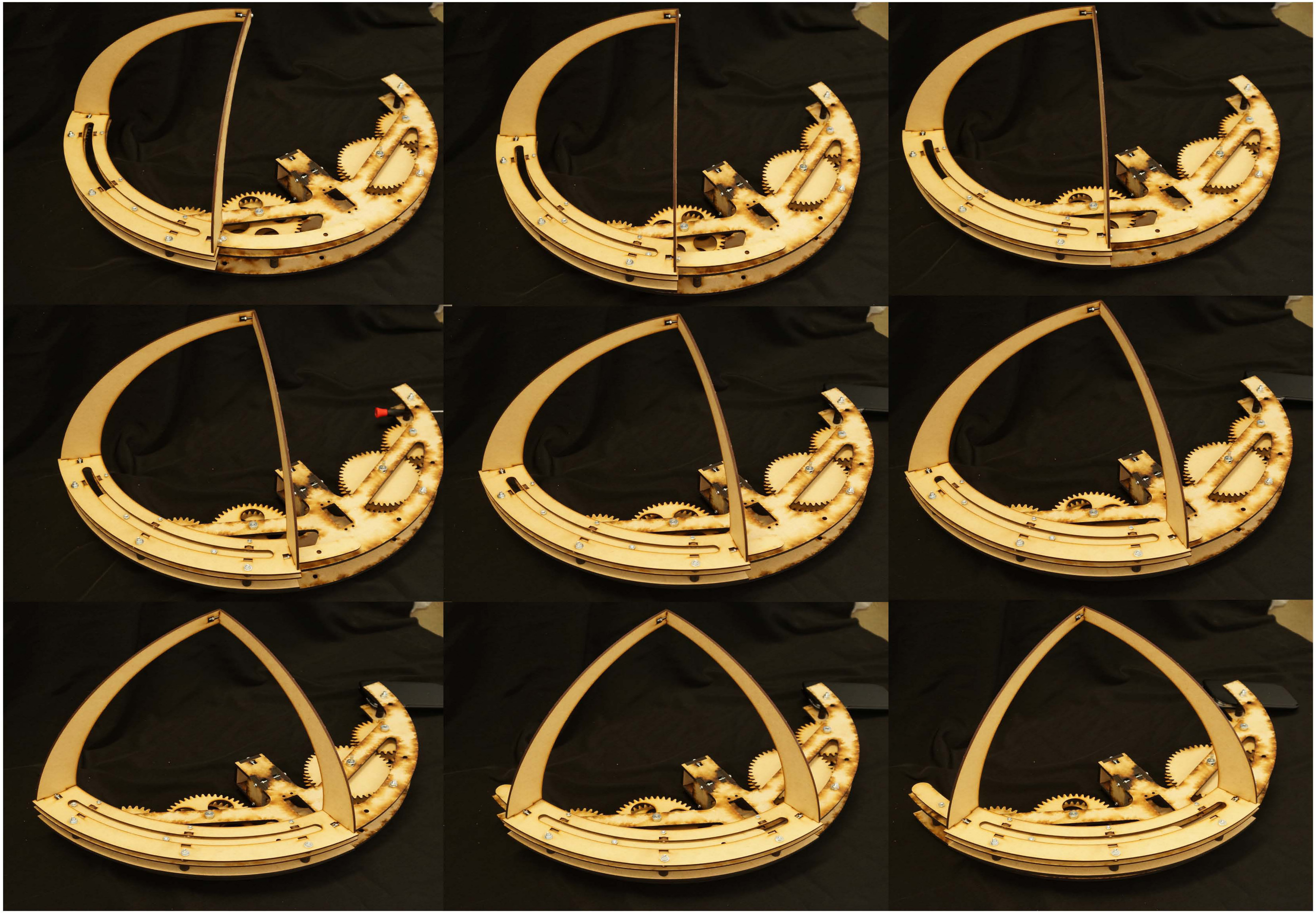


ROTATION OF THE OUTSIDE SPHERE

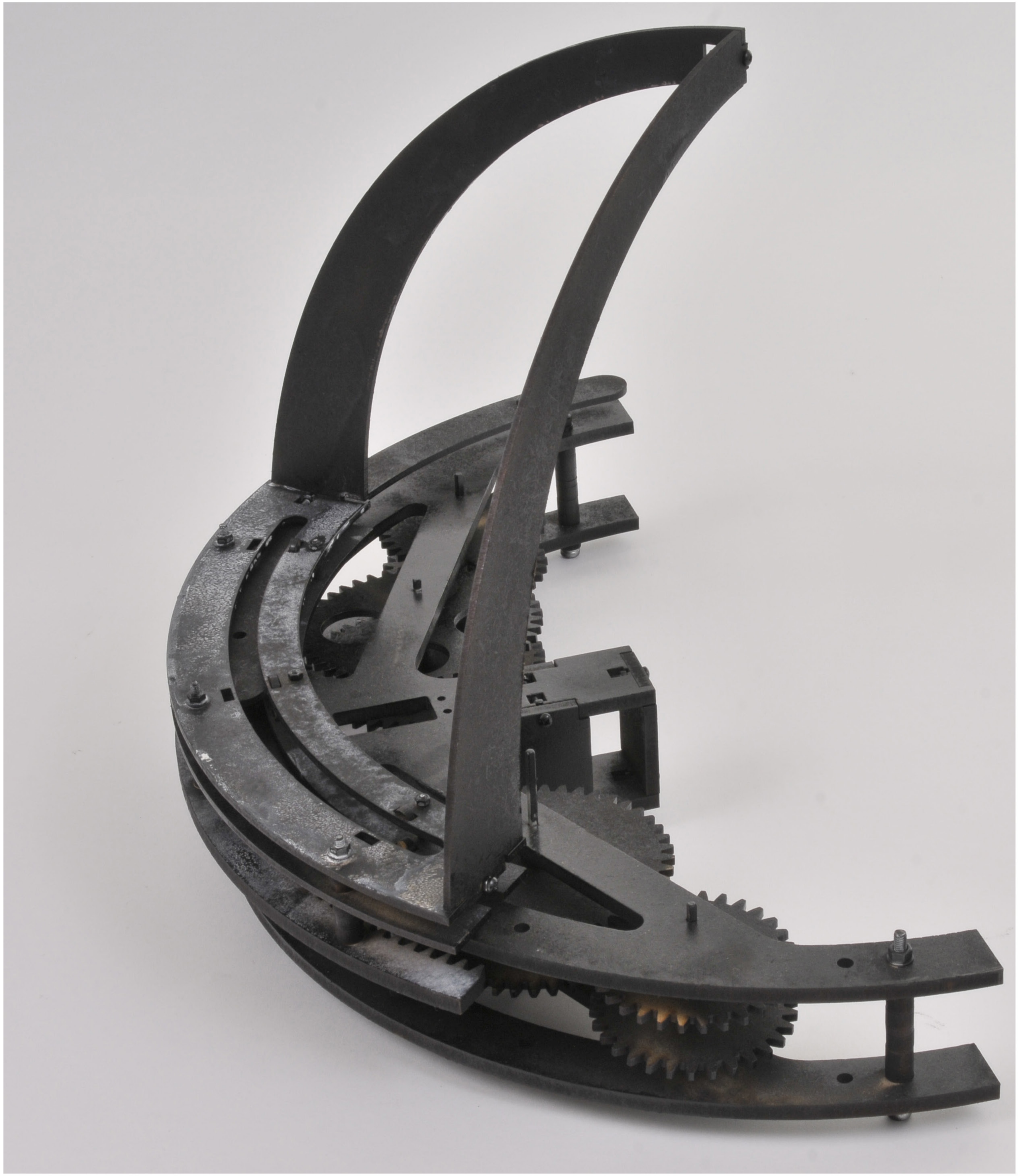




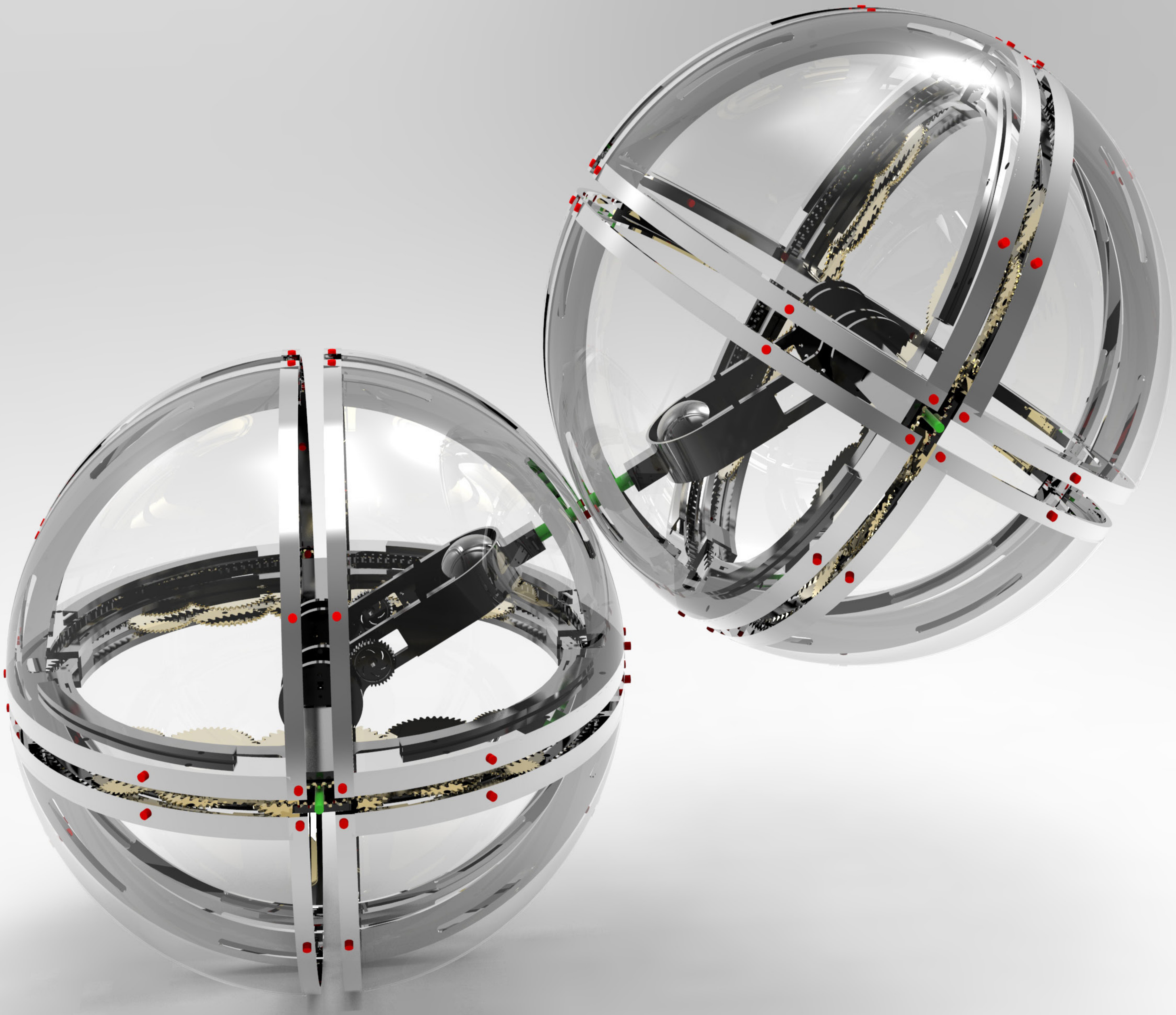




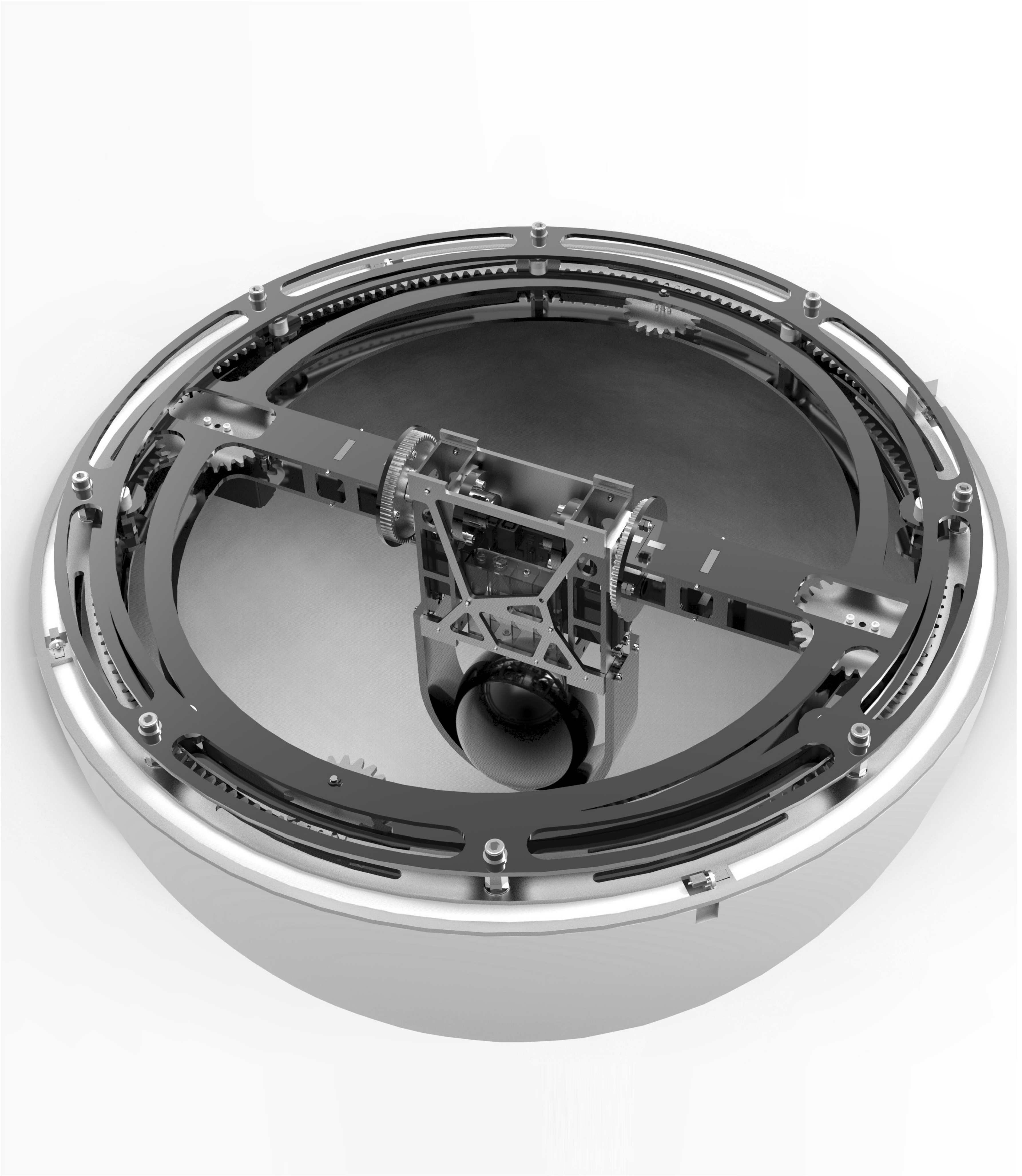
BREAK THE SPHERE AND STILL CAN ROTATE (1/4 PARTS OF THE PROTOTYPE)

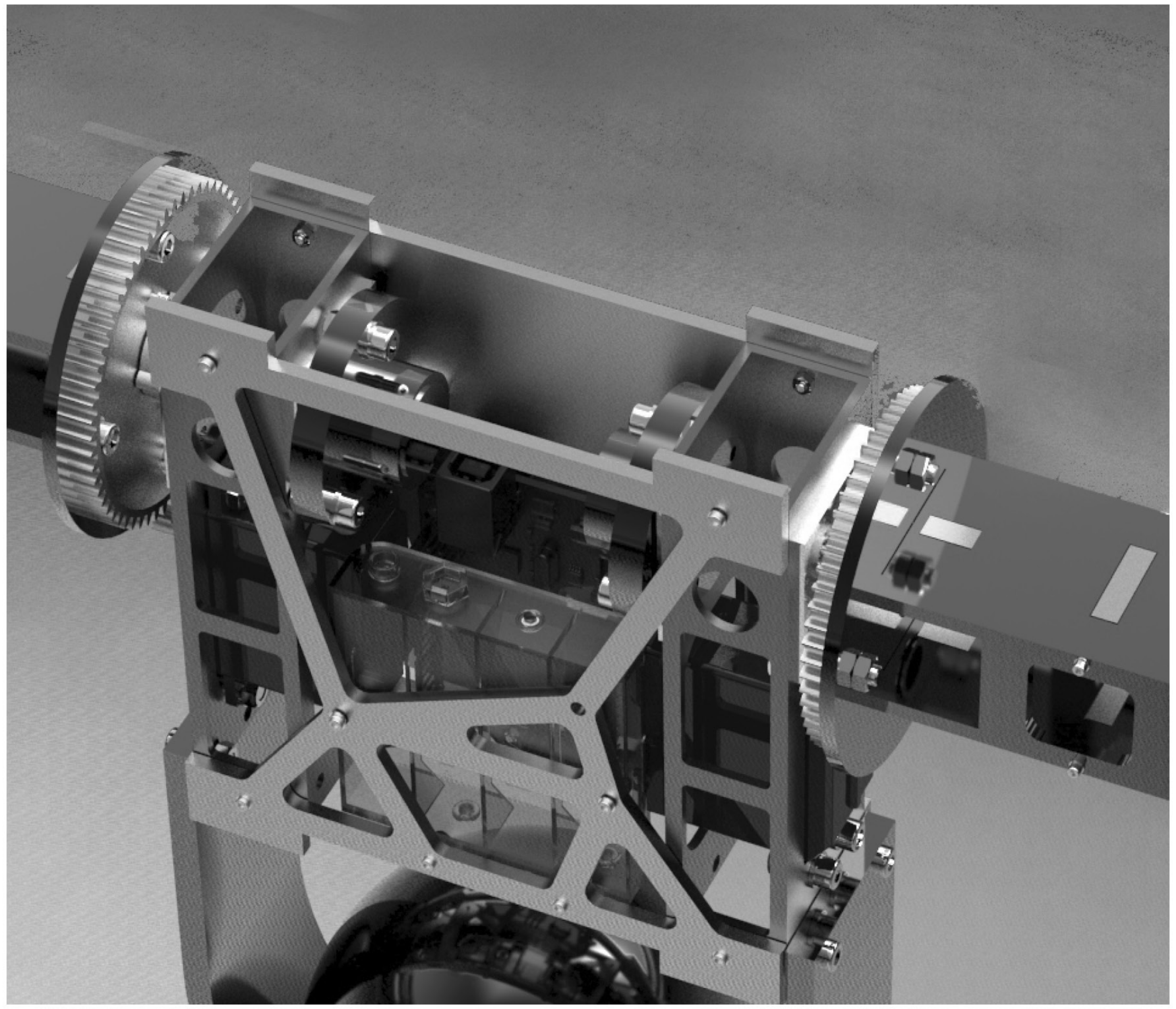


DESIGN FOR SELF- ASSEMBLY

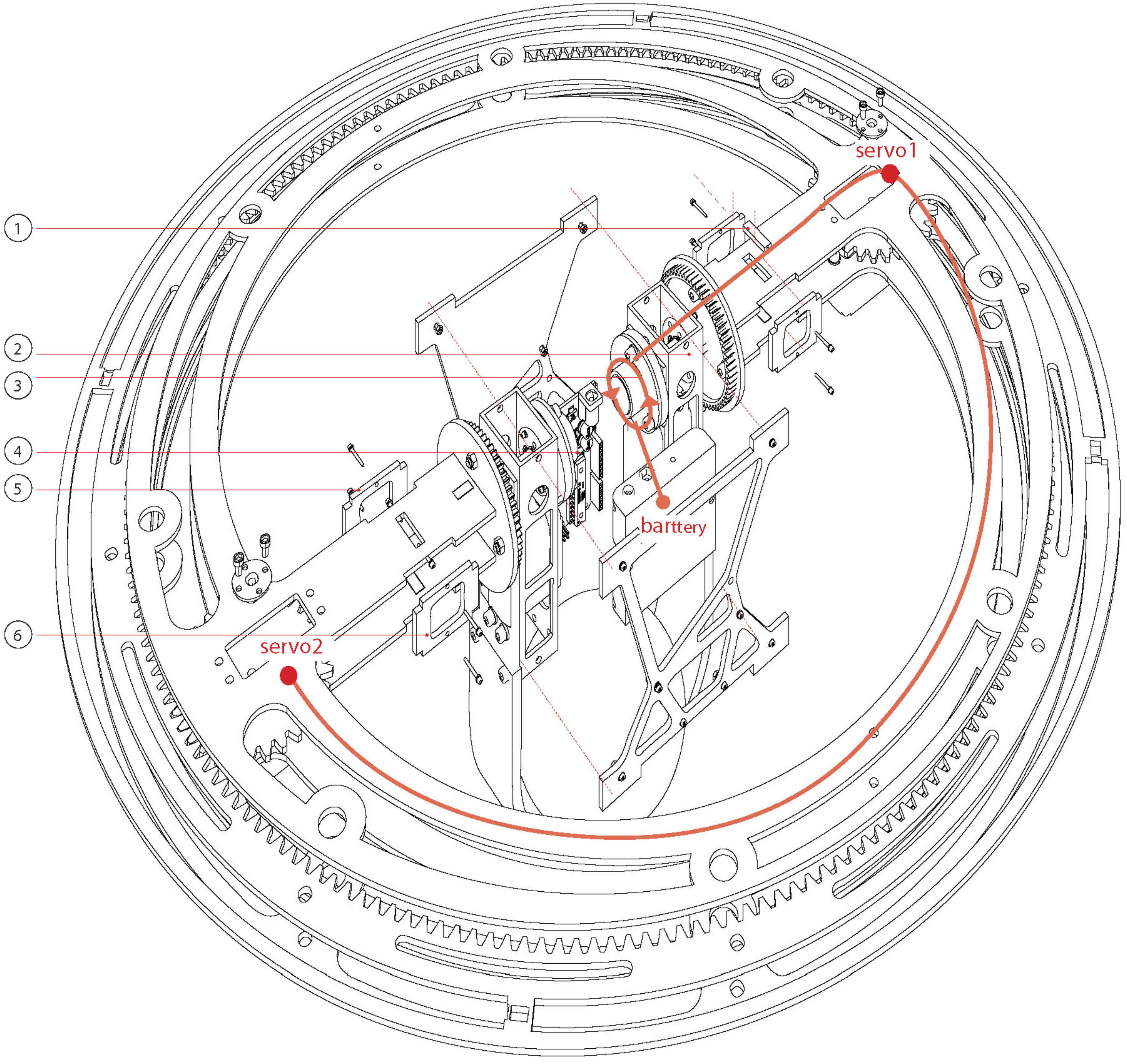


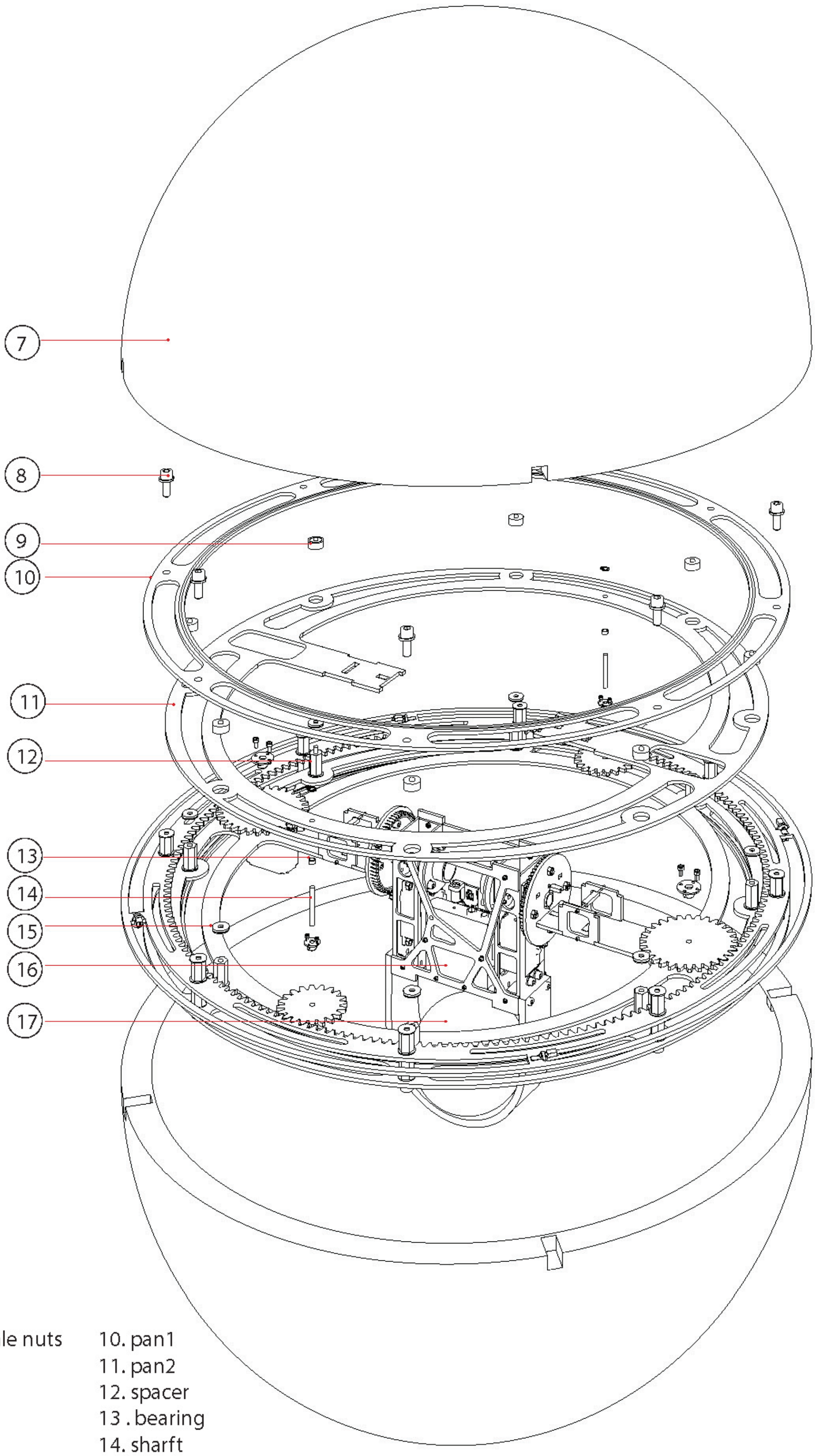
PROTOTYPE4 MECHANISM IMPROVED HOLLOW THE SHAFT





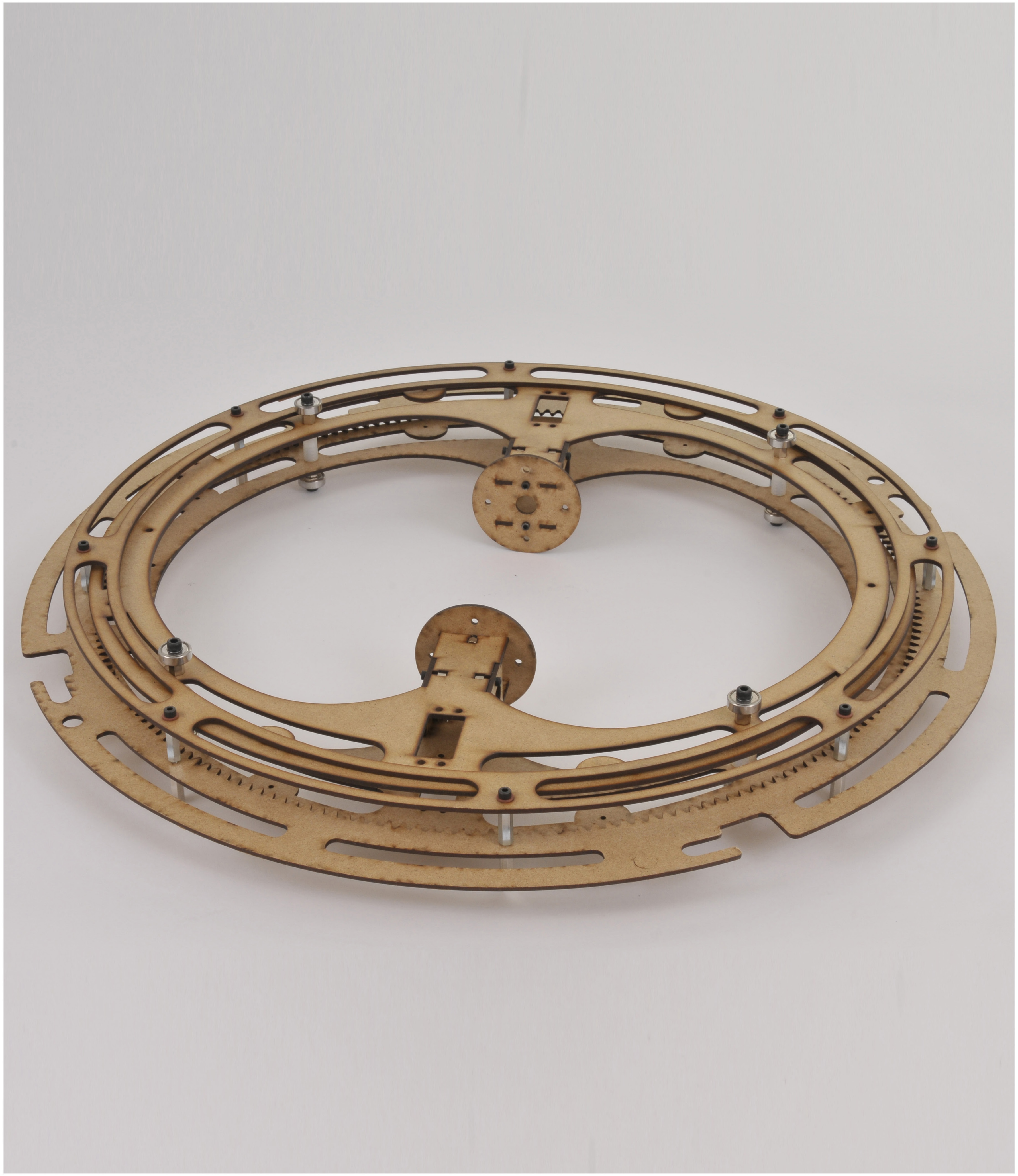
PROTOTYPE4 MECHANISM

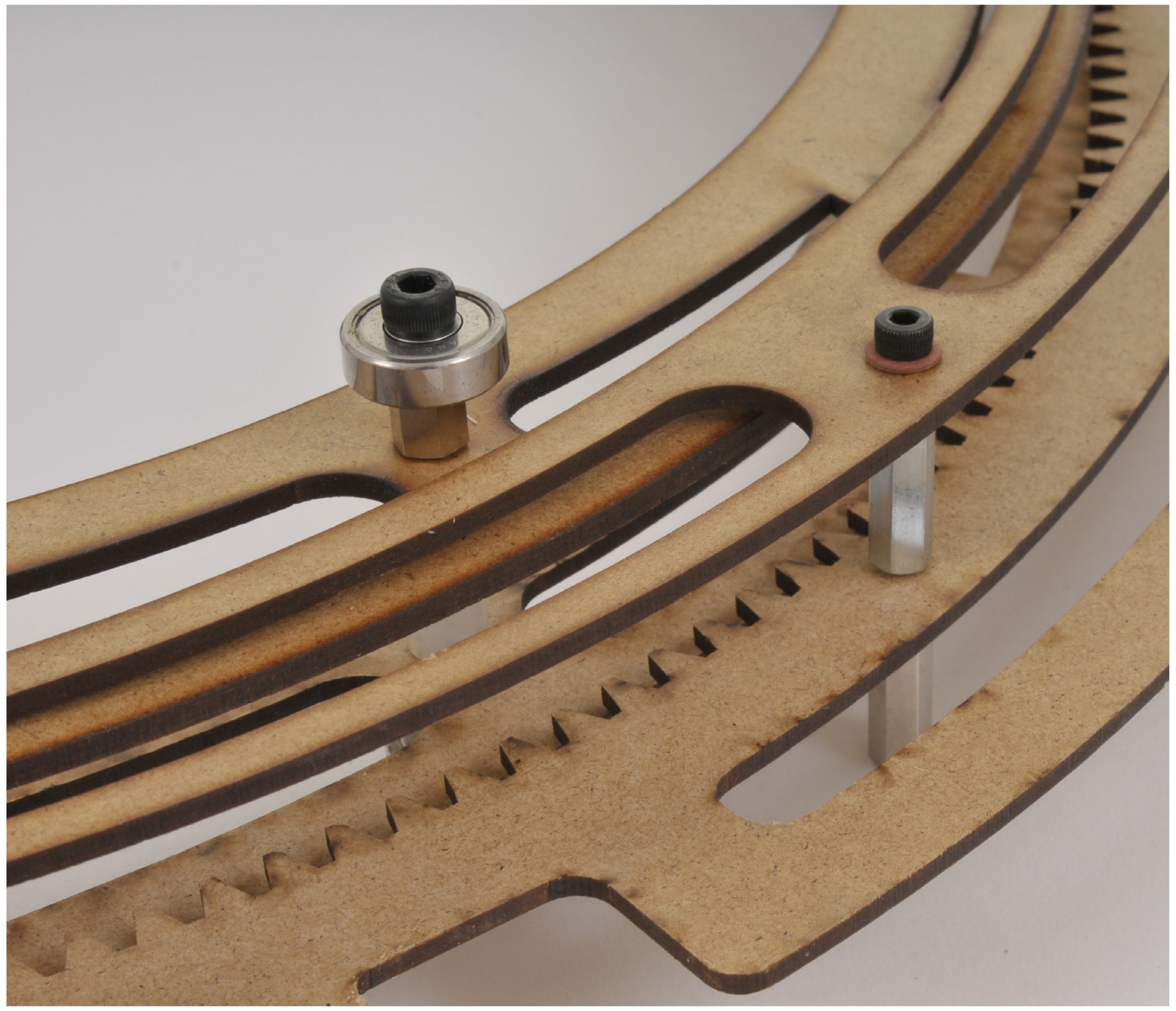




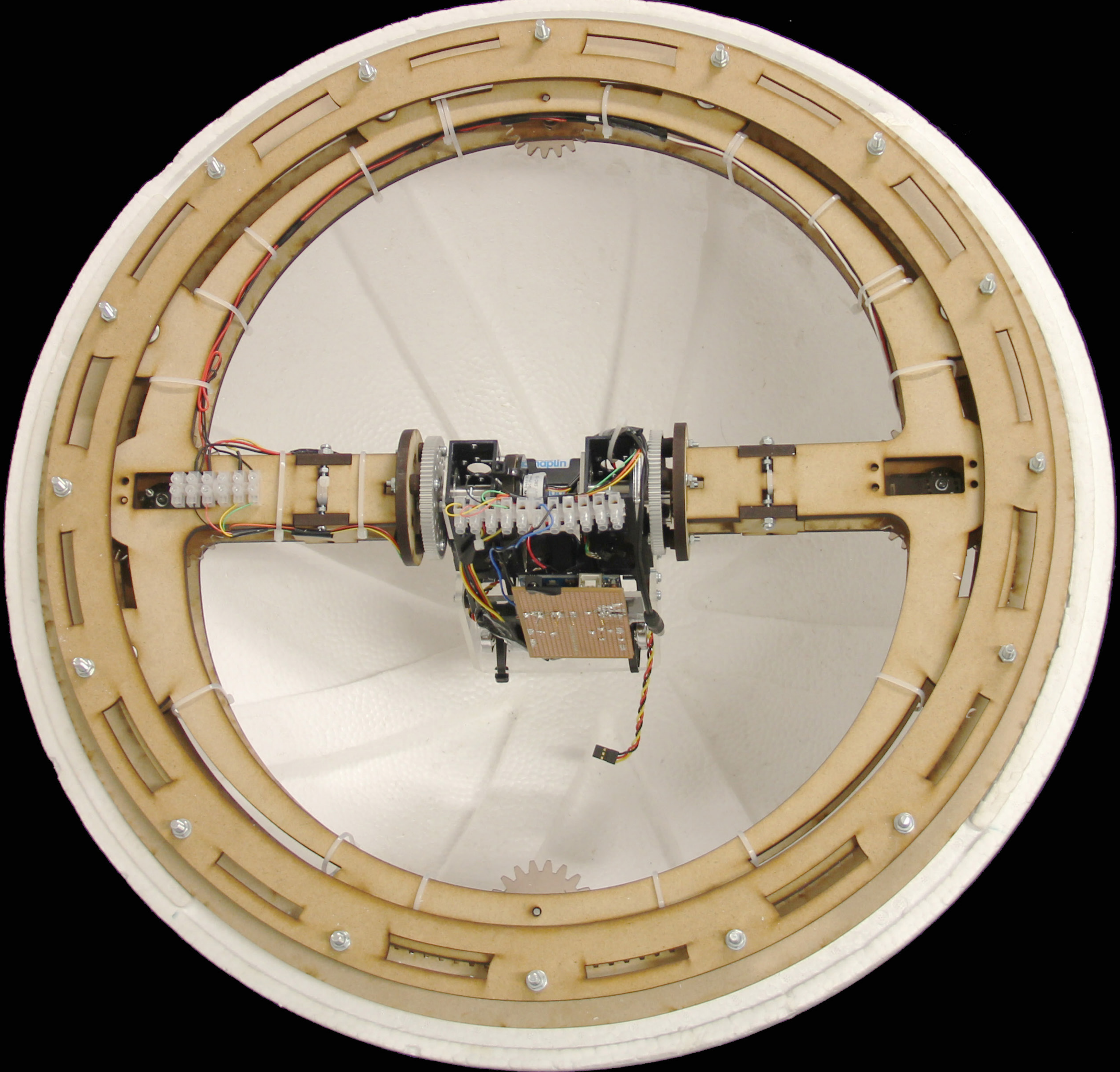
1. female female nuts
2. servo box 15
3. slip ring
4. arduino
5. m3 screw
6. support
7. hemisphere
8. m4 screw
9. transport ball
10. pan1
11. pan2
12. spacer
13. bearing
14. sharft
15. washer
16. battery box
17. weight mass

PROTOTYPE4 MODEL

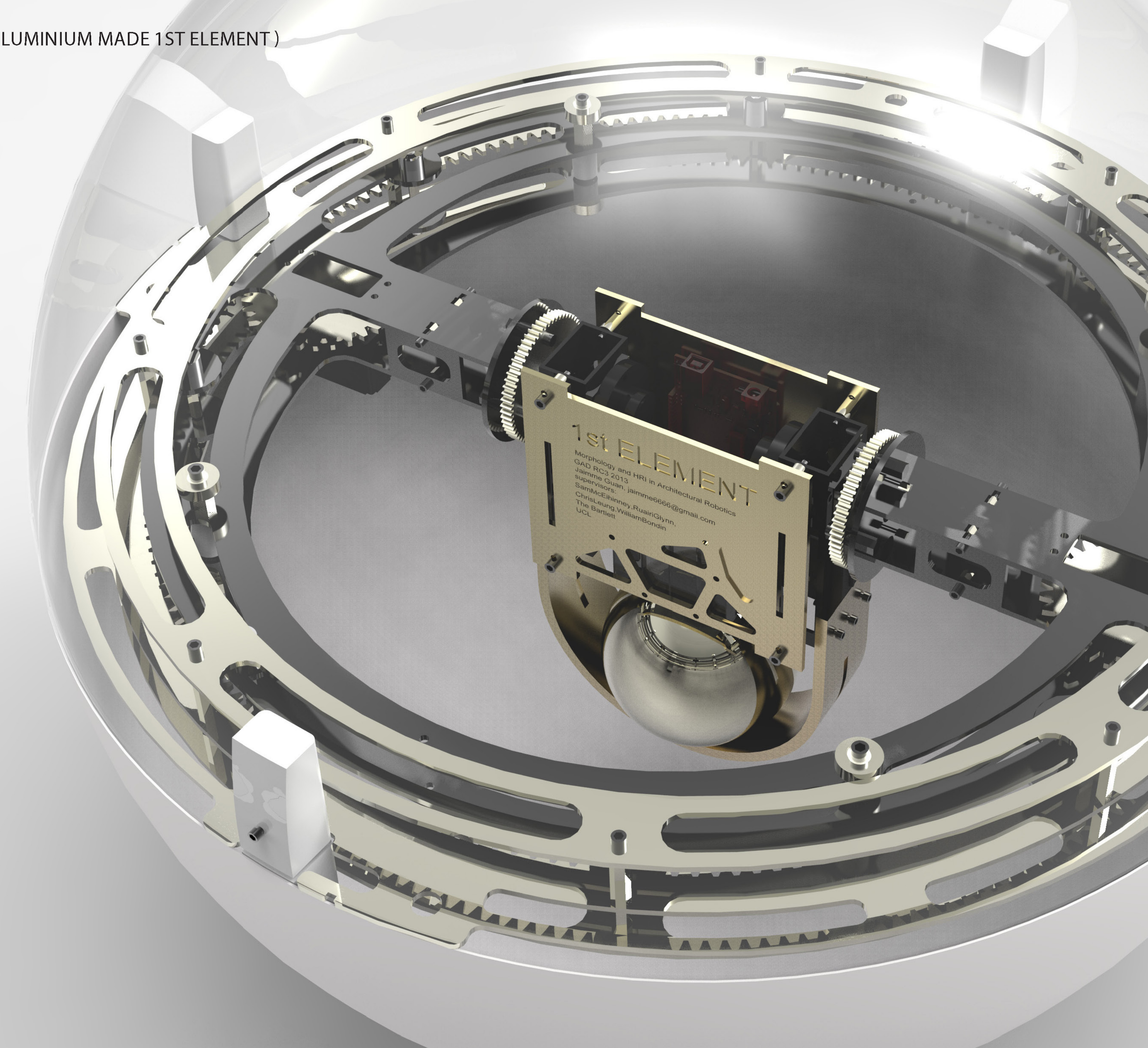




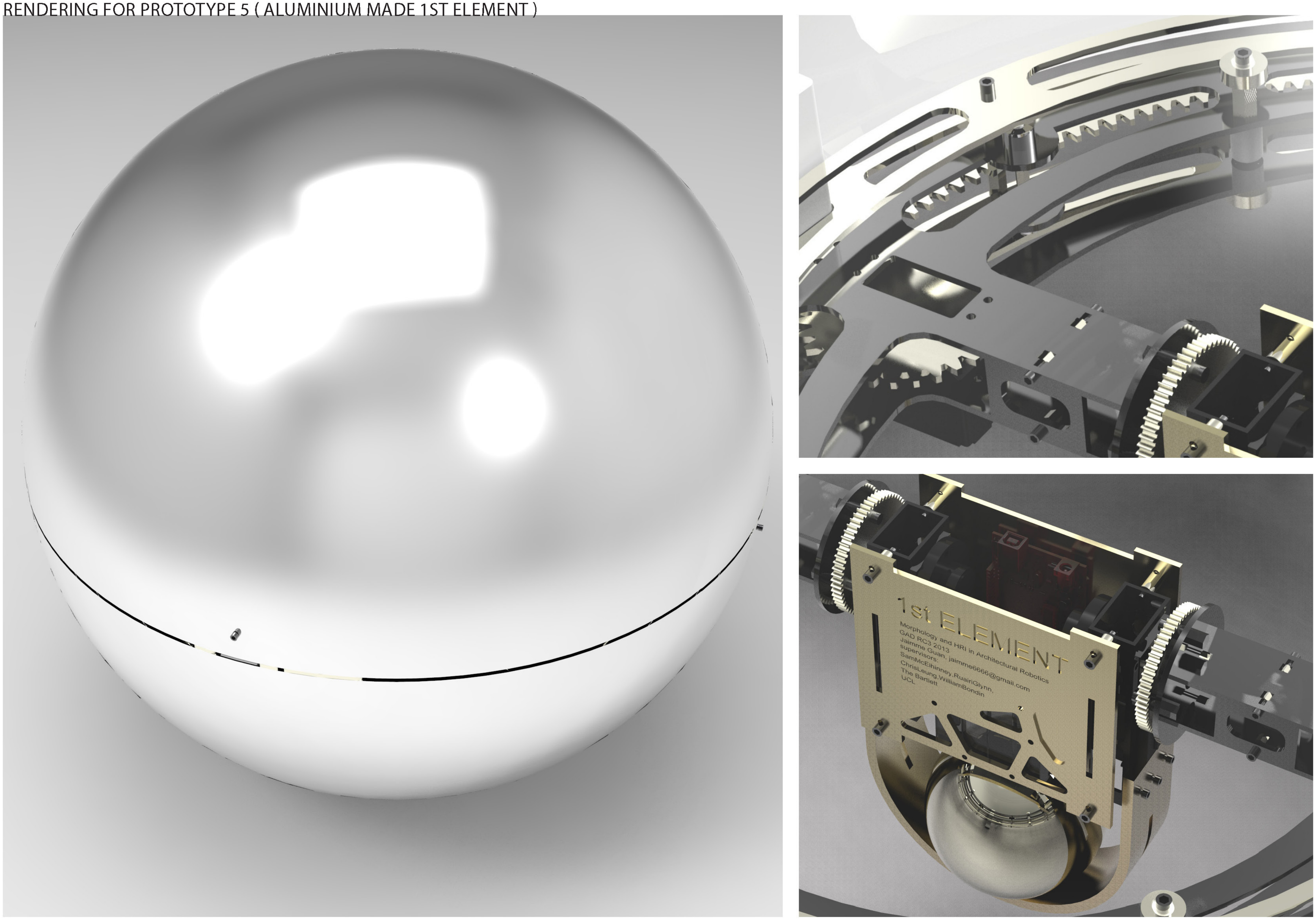
PROTOTYPE4 MODEL



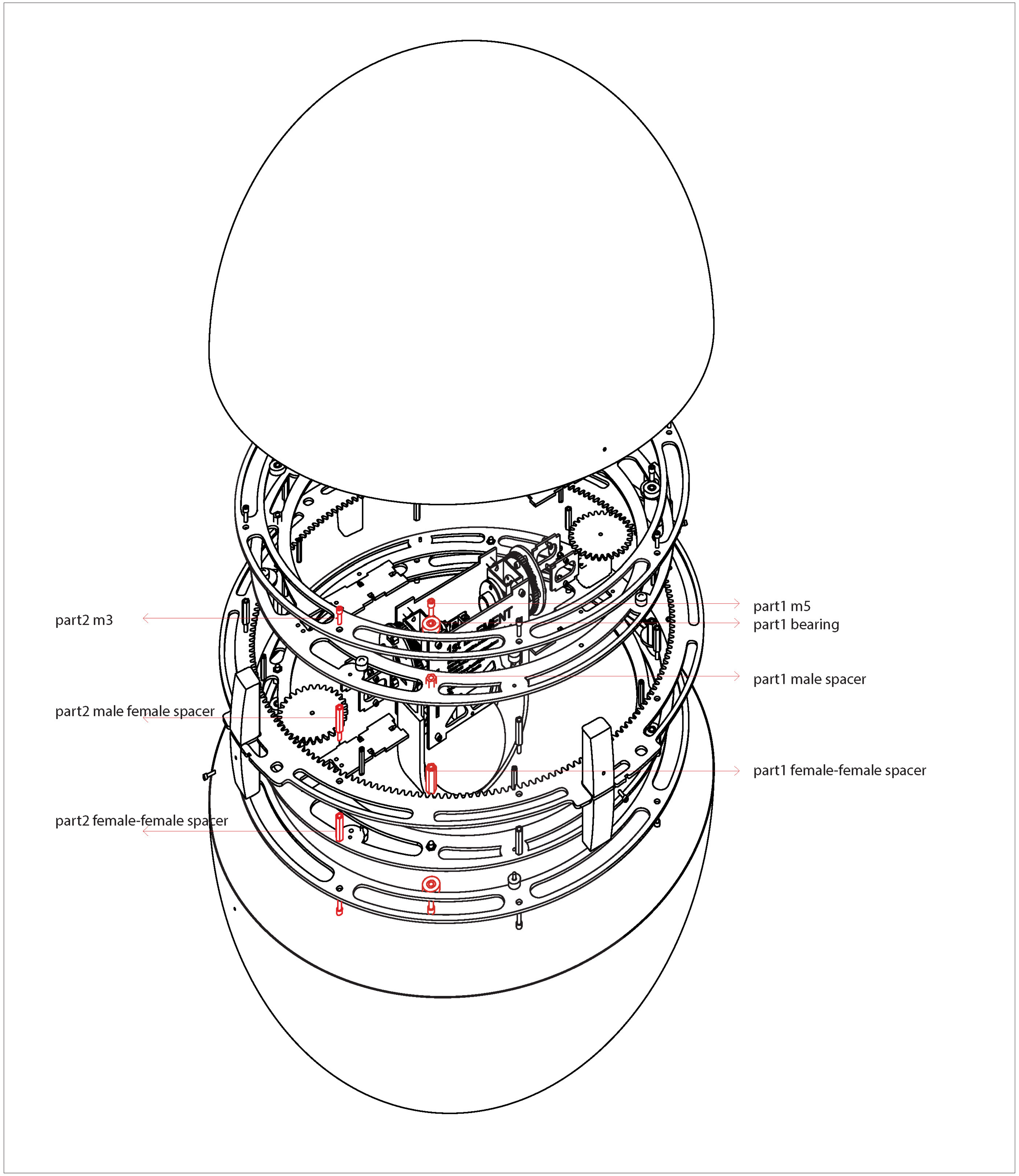
RENDERING FOR PROTOTYPE 5 (ALUMINIUM MADE 1ST ELEMENT)

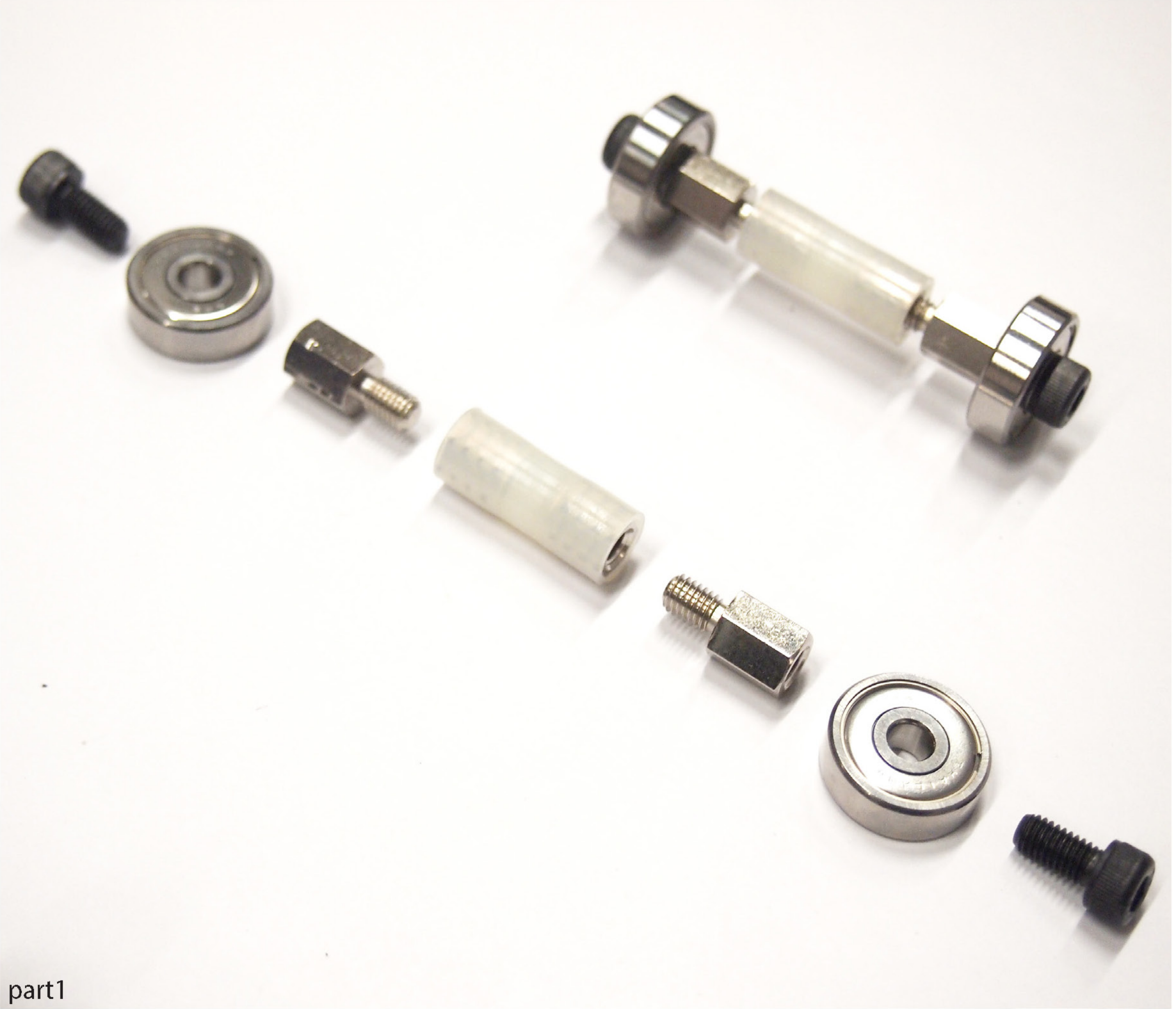

1st ELEMENT
Morphology and HRI in Architectural Robotics
GAD RC3 2013
Jaimme Guan, jaimme6666@gmail.com
supervisors:
SamMcElhinney,RuairiGlynn,
ChrisLeung,WilliamBondin
The Bartlett
UCL

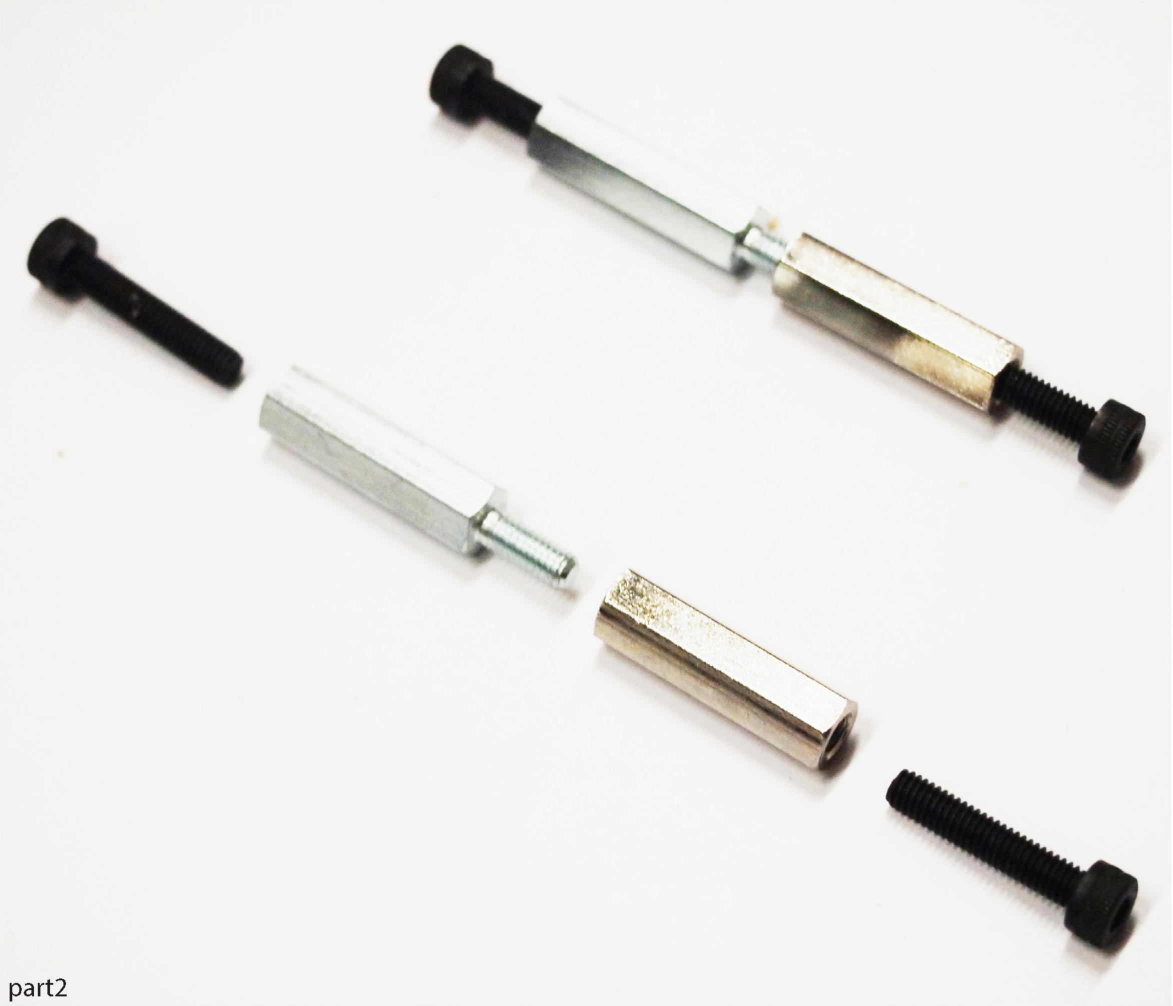
RENDERING FOR PROTOTYPE 5 (ALUMINIUM MADE 1ST ELEMENT)


1st ELEMENT
Morphology and HRI in Architectural Robotics
GAD RC3 2013
Jaimme Guan, jaimme6666@gmail.com
supervisors:
SamMcElhinney,RuairiGlynn,
ChrisLeung,WilliamBondin
The Bartlett
UCL

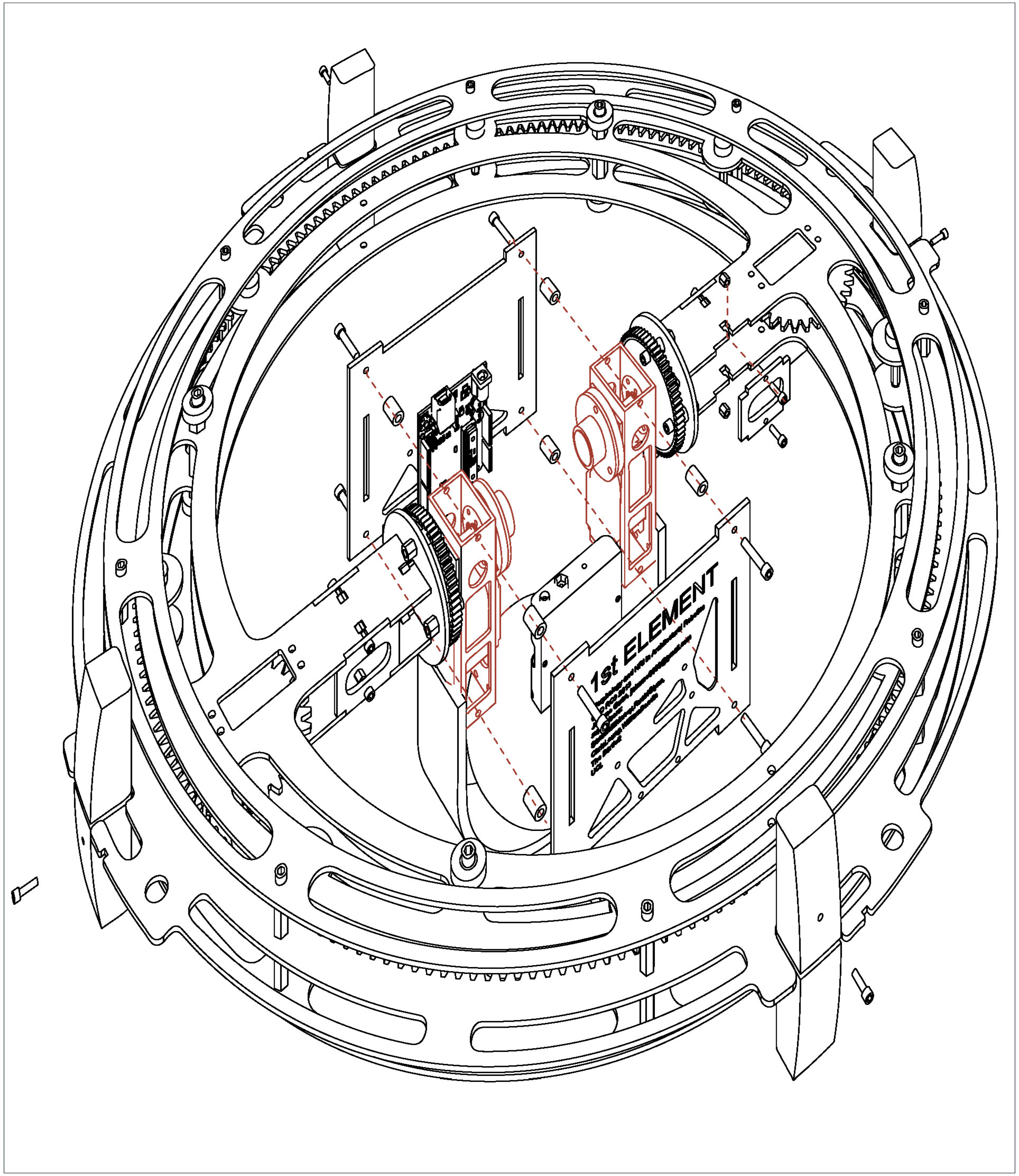
PROTOTYPE5 MECHANISM (THE 1ST ELEMENT)

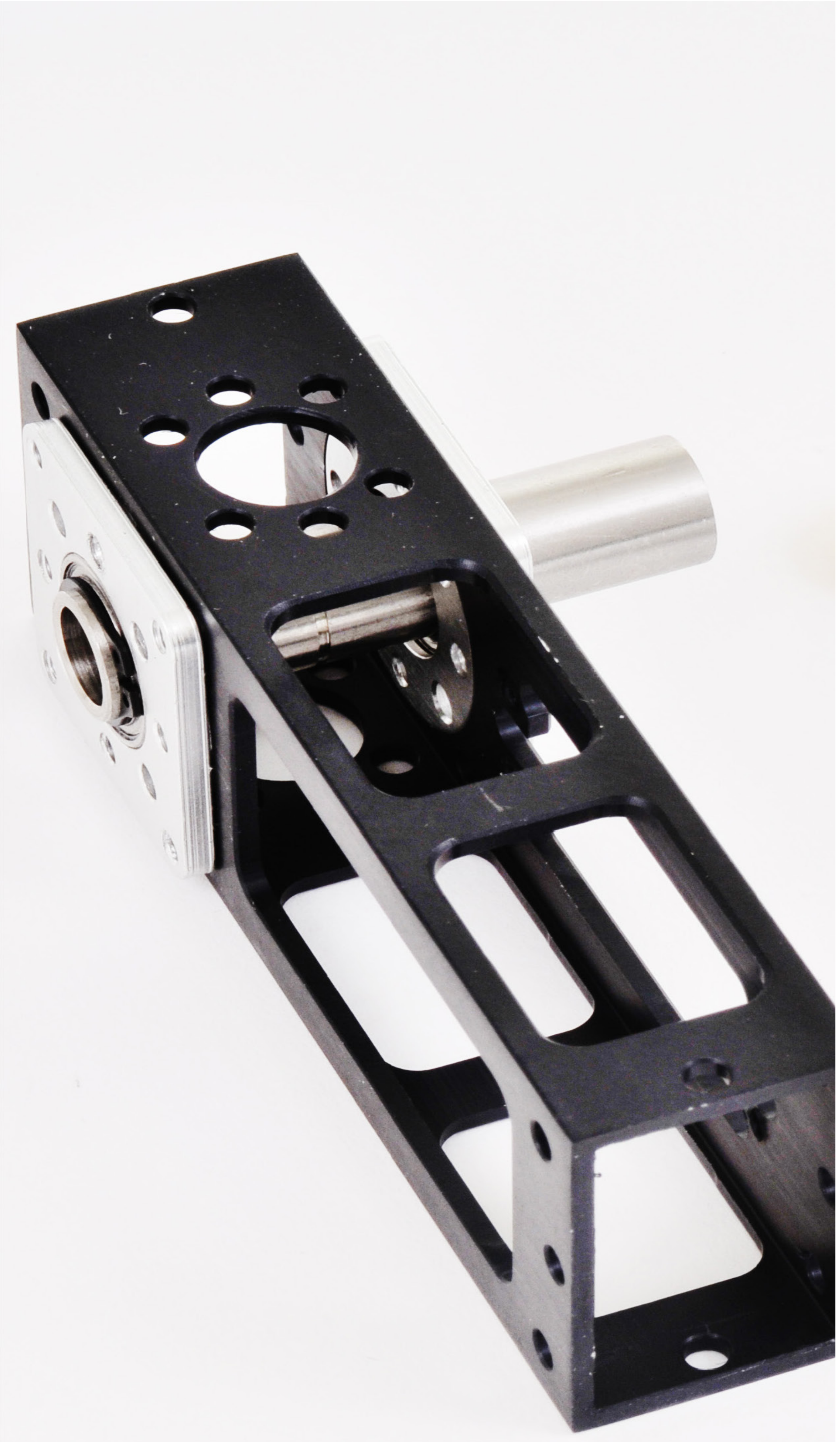



part1

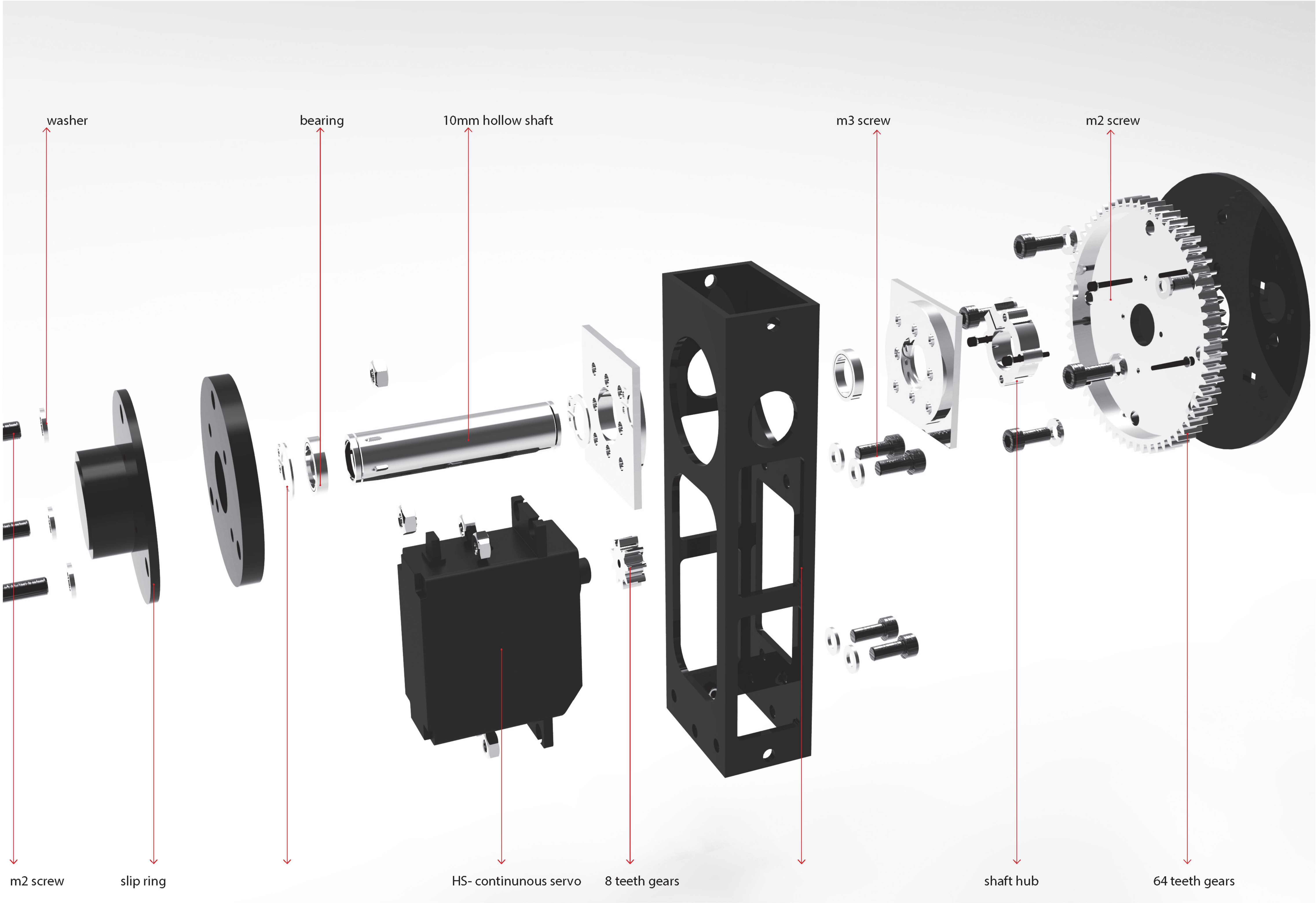

part2

PROTOTYPE5 MECHANISM (THE 1ST ELEMENT)

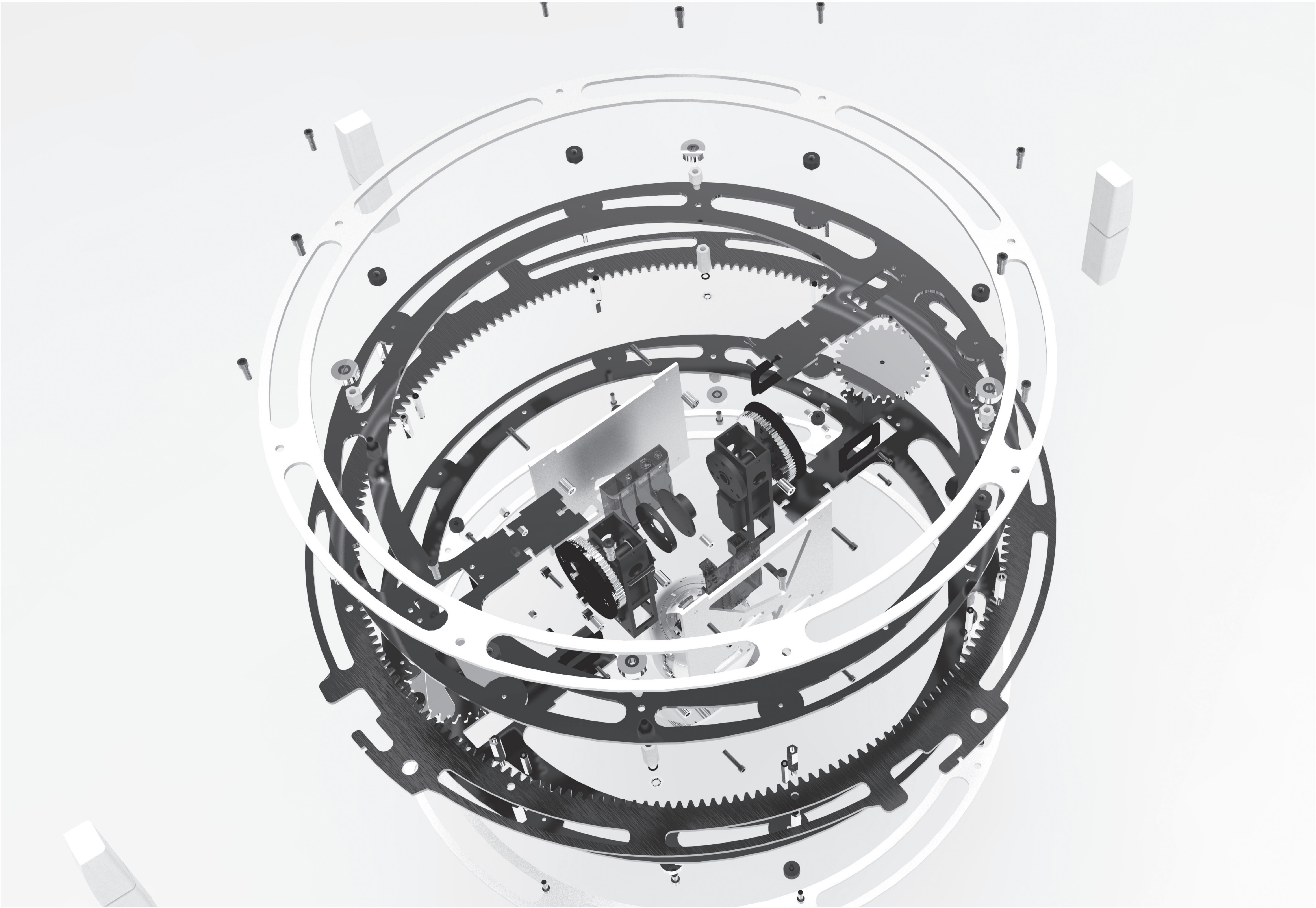



servo box

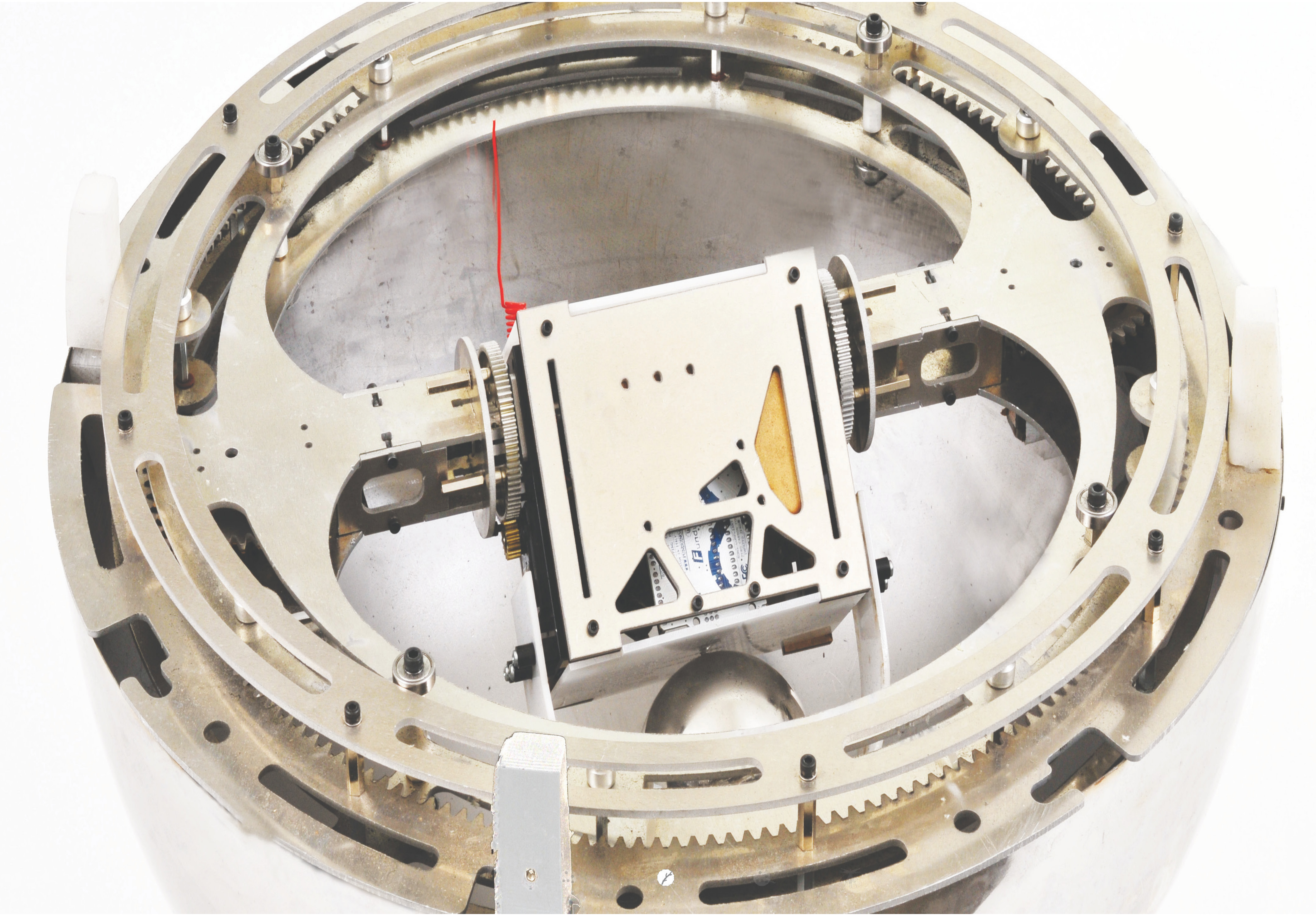
ASSEMBLY OF SERVO BOX



ASSEMBLY OF 1ST ELEMENT

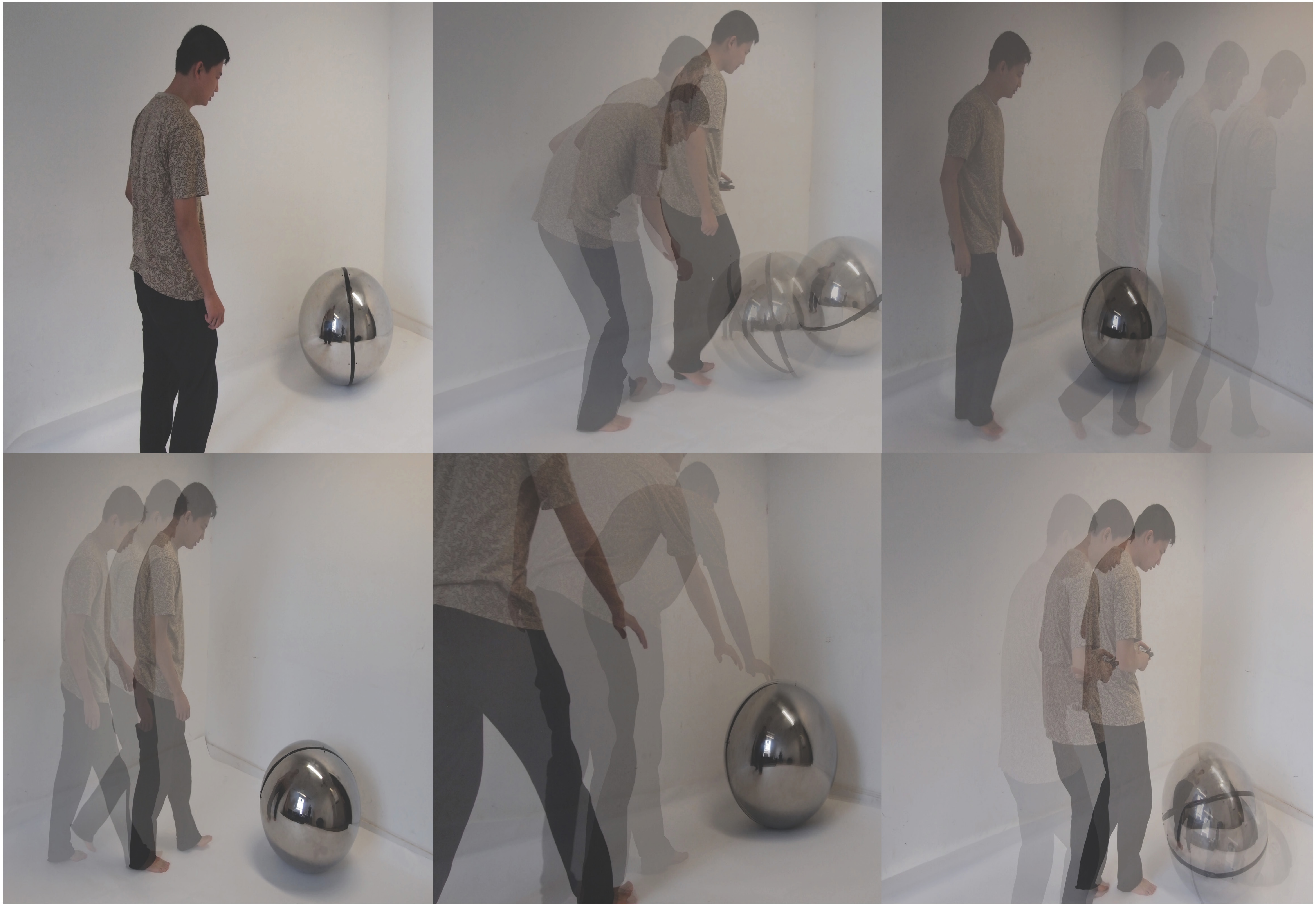


MAKING OF 1ST ELEMENT



1ST ELEMENT IN UCL

PHYSICAL PROXEMICS ALSO EXISTED IN HUMAN ROBOT INTERACTION(HRI)

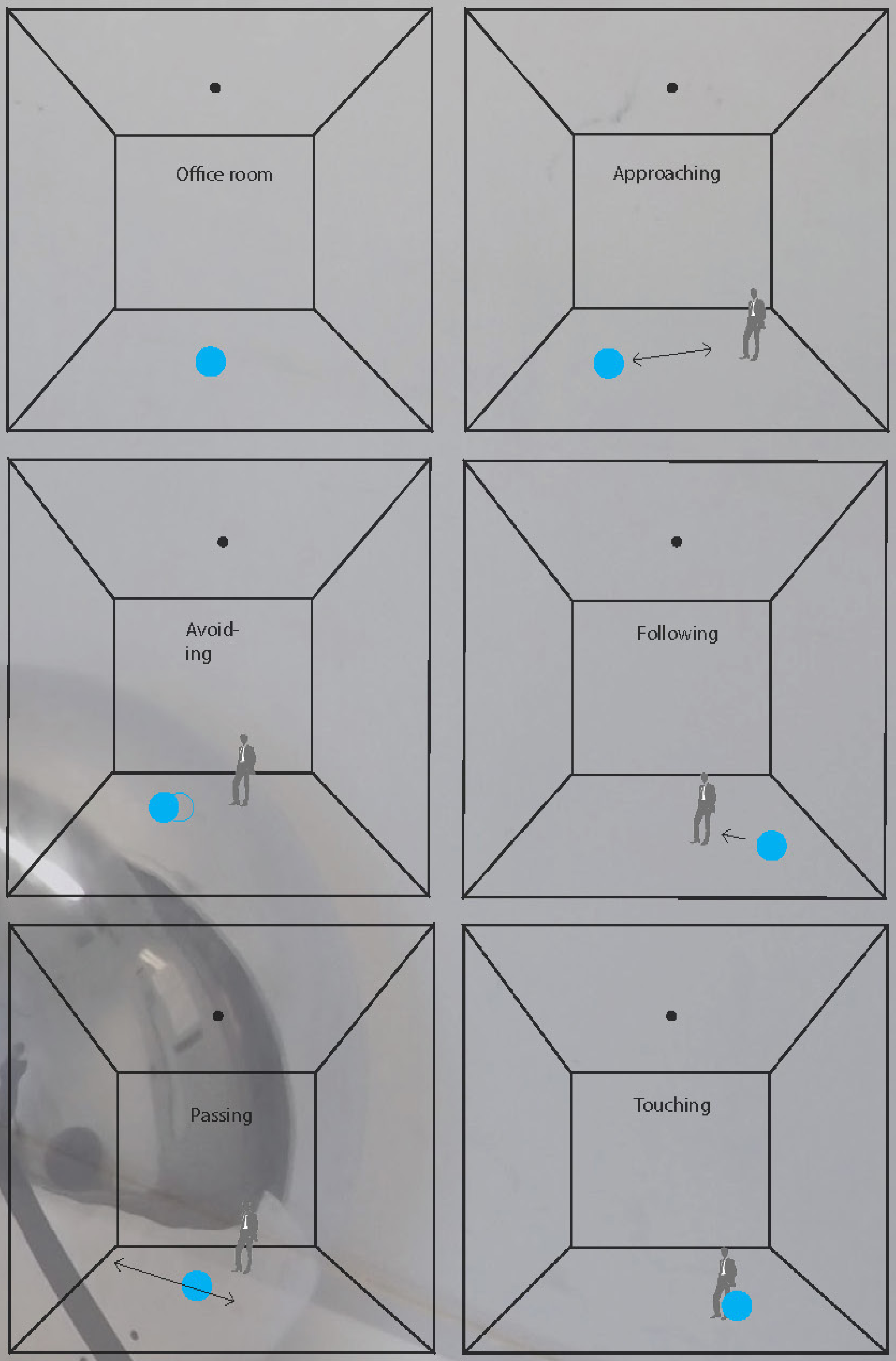


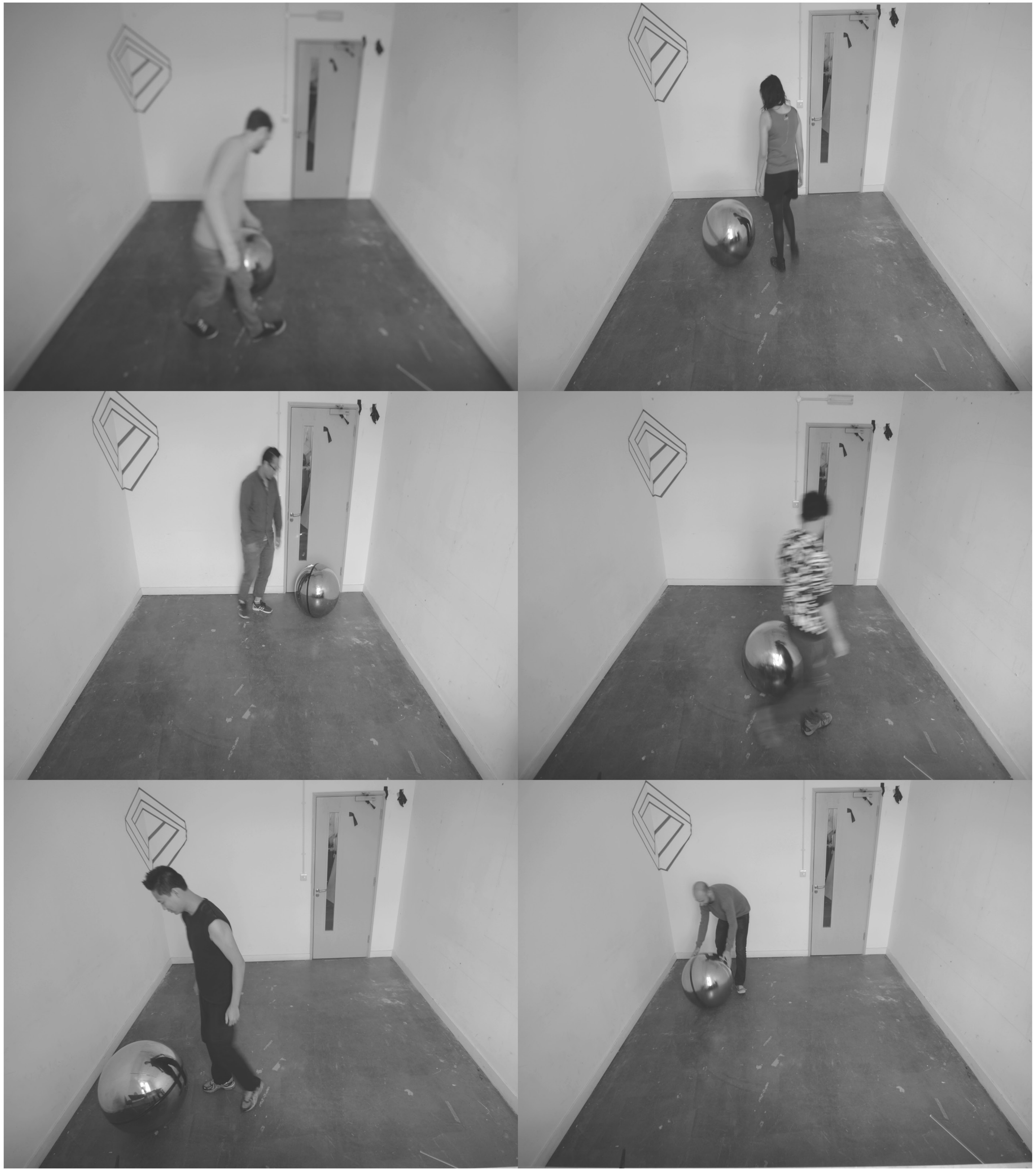
OBSERVATION OF THE PROXEMICS BEHAVIOUR WITH RF CONTROL

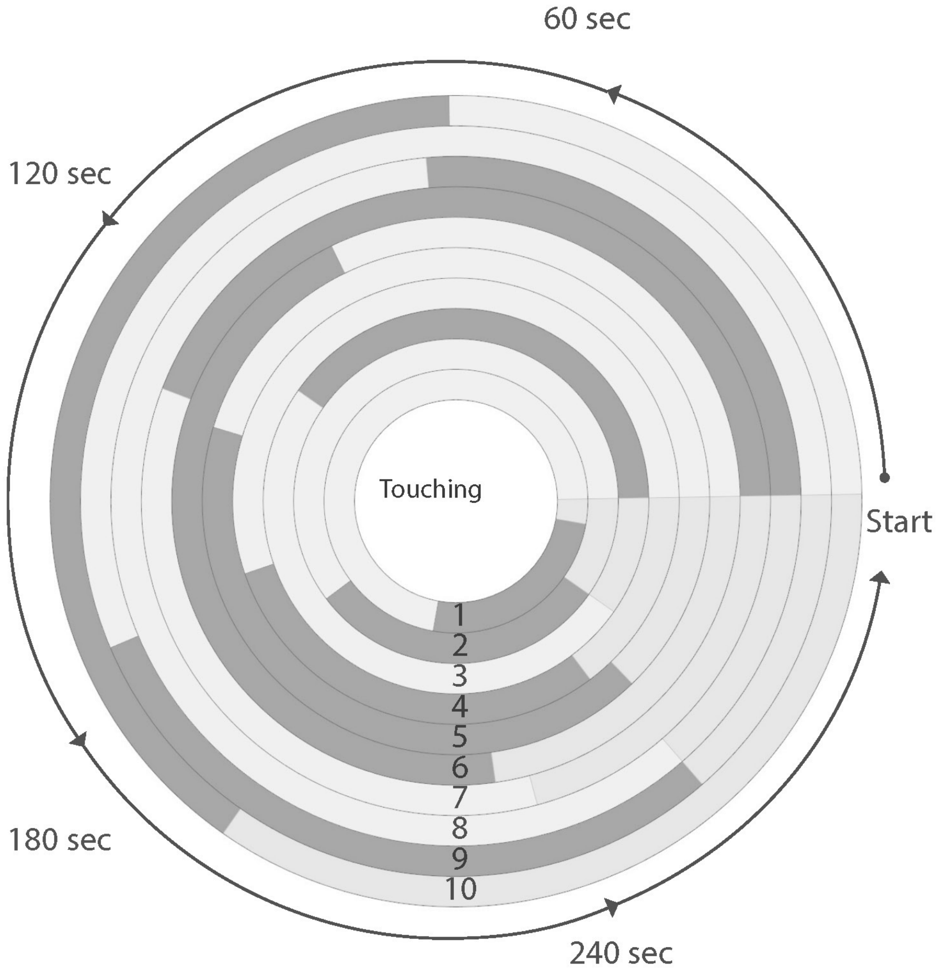
Goal of the observation:
to explore if certain proximity behaviours of the robot can trigger the relevant proximity behaviour of a human

Values of the observation:
behaviours in the HRI, we used the following values as representing the behaviours:
(1) AV------------------------------(avoiding)
(2) P -----------------------------(passing)
(3) AP--------------------------(approaching)
(4) F -----------------------------(following)
(5) T ------------------------------(touching)
(6) TIME--(period of the certain behaviour)

Method of the observation:
Each experimental session followed the same format:
1)Invite a participant into the room.
2)The robot begins to perform a single type of proximity behaviour
towards the participant (from the five behaviours offered above) for a five-minute period.
3) recording the reaction of the participants by camera.

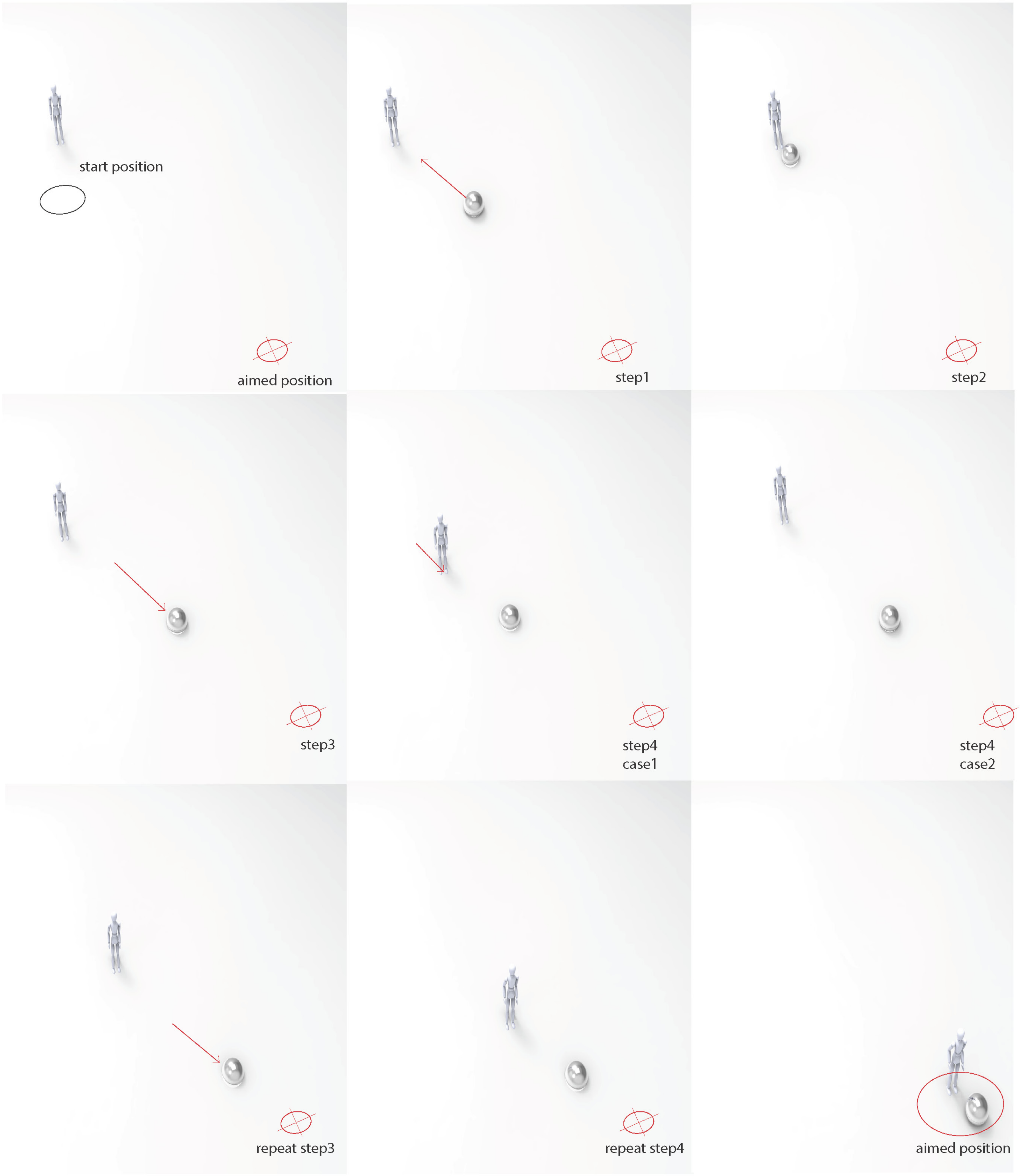


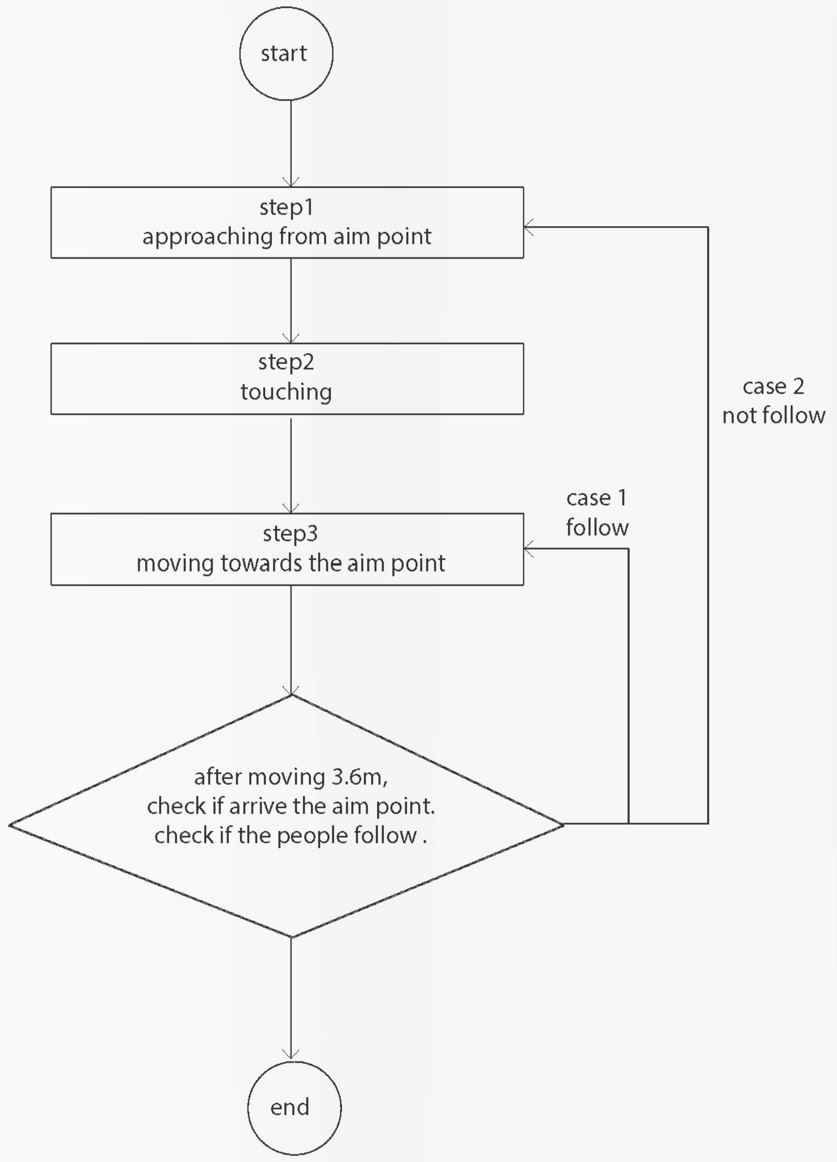




Participants show similar reactions as the robot-approaching and robot-following sessions, but most of them try to touch it back

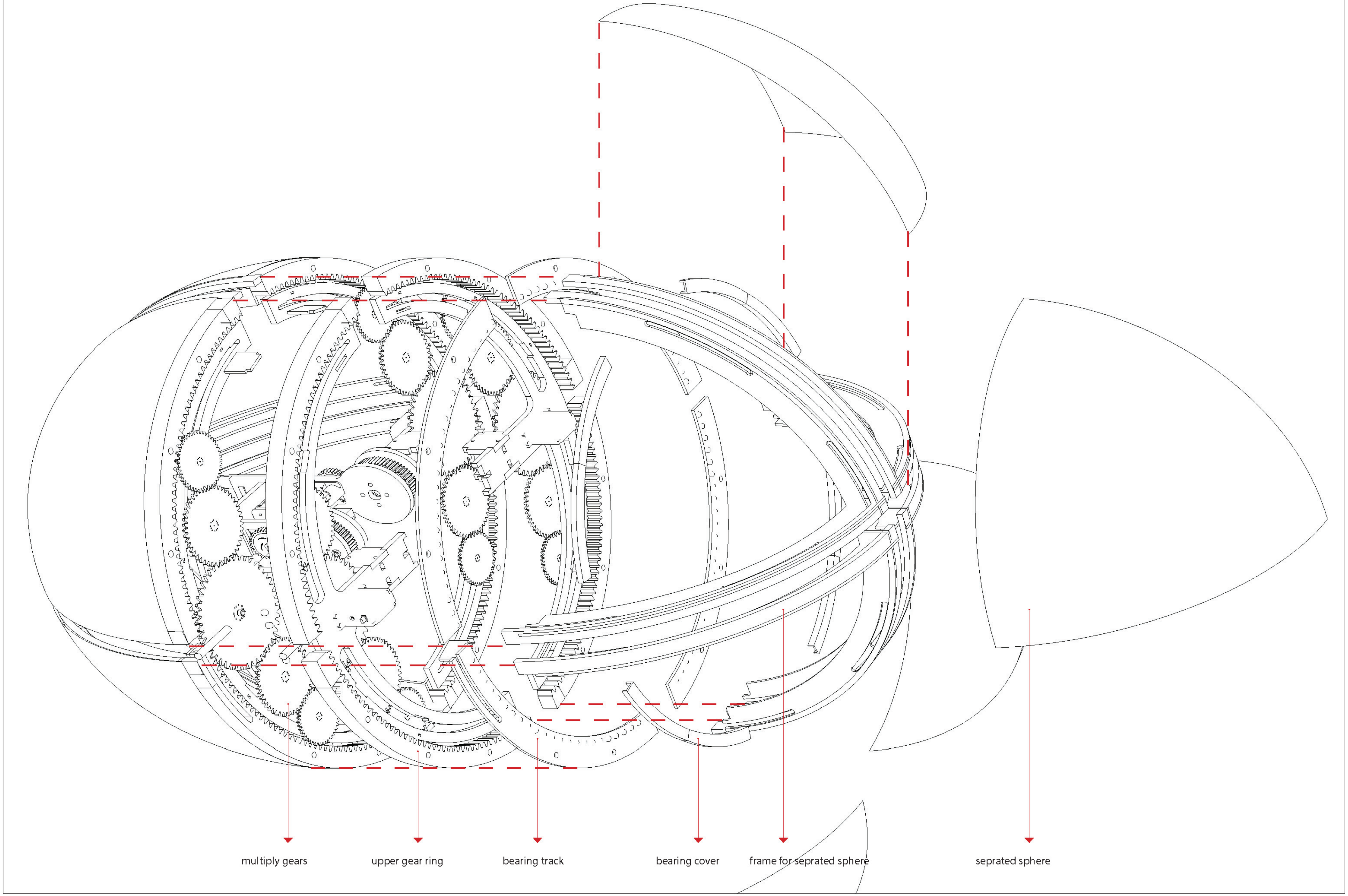
BASED ON THE RESULT OF OBSERVATION, DESIGN A LAW FOR ROBOT TO TRACK PEOPLE



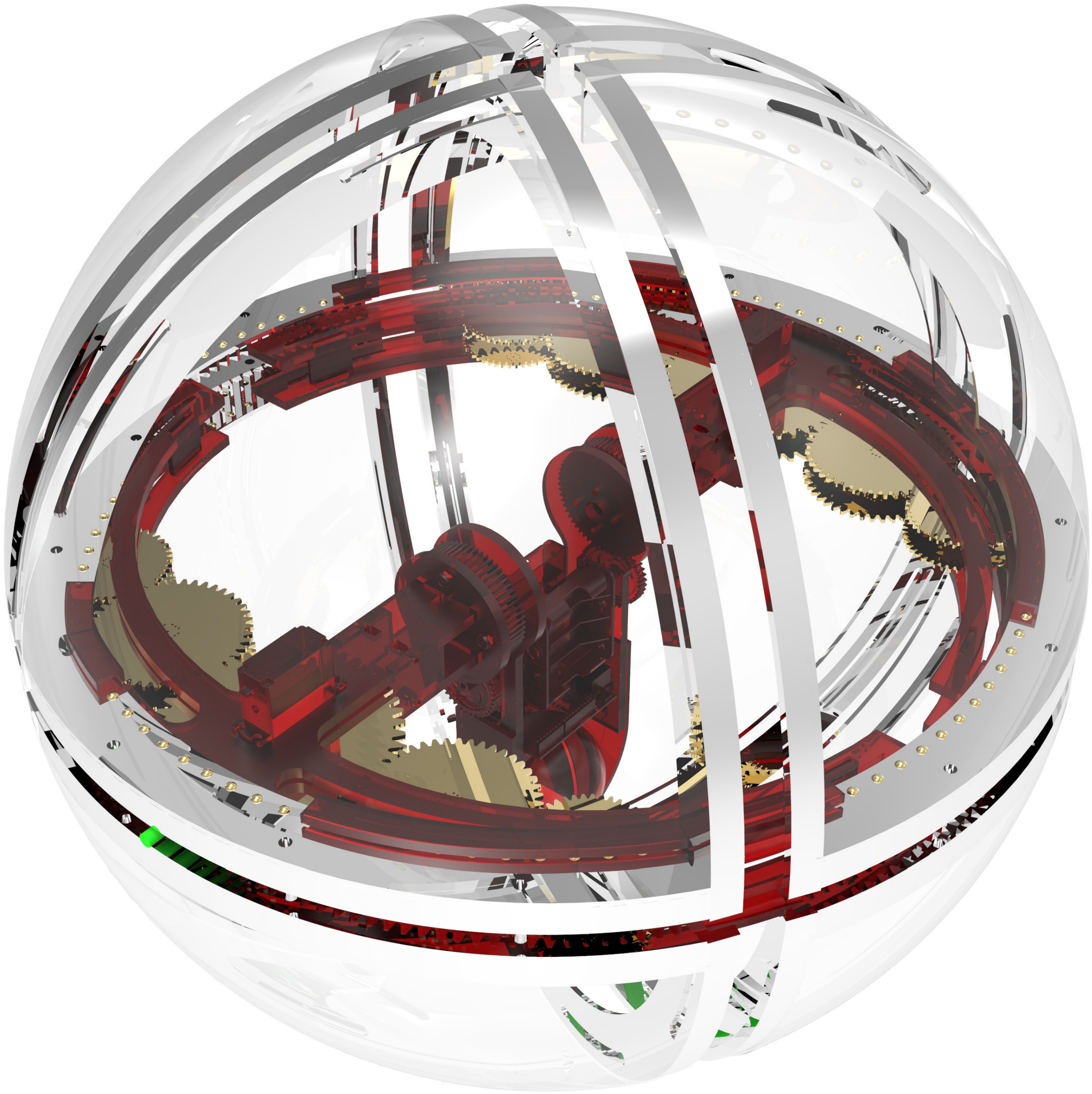

start
step1
approaching from aim point
step2
touching
step3
moving towards the aim point
after moving 3.6m,
check if arrive the aim point.
check if the people follow .
case 1
follow
case 2
not follow
end

THE "ELEMENT" IN INDOOR SPACE

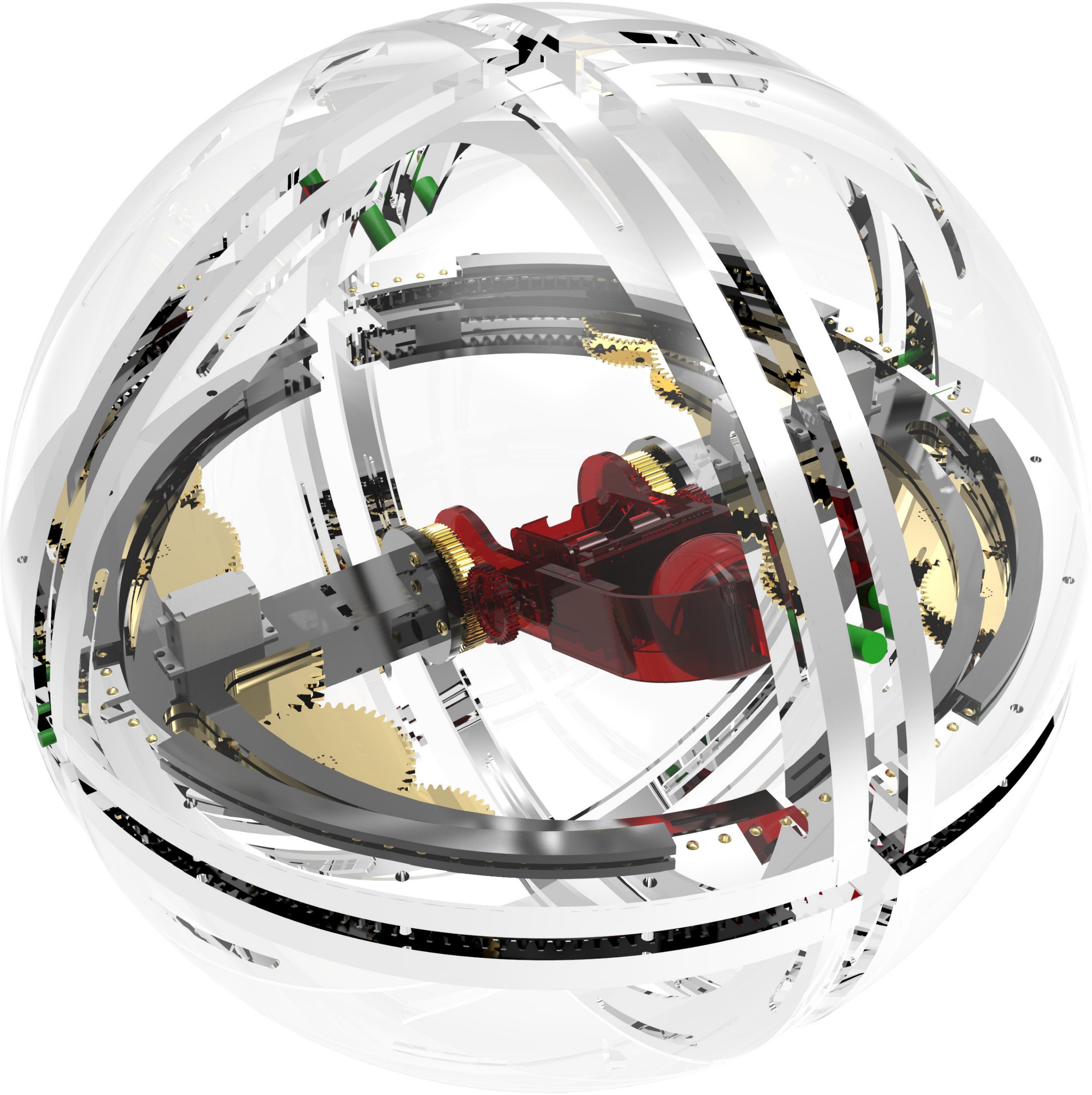
DESIGN FOR SELF- ASSEMBLY



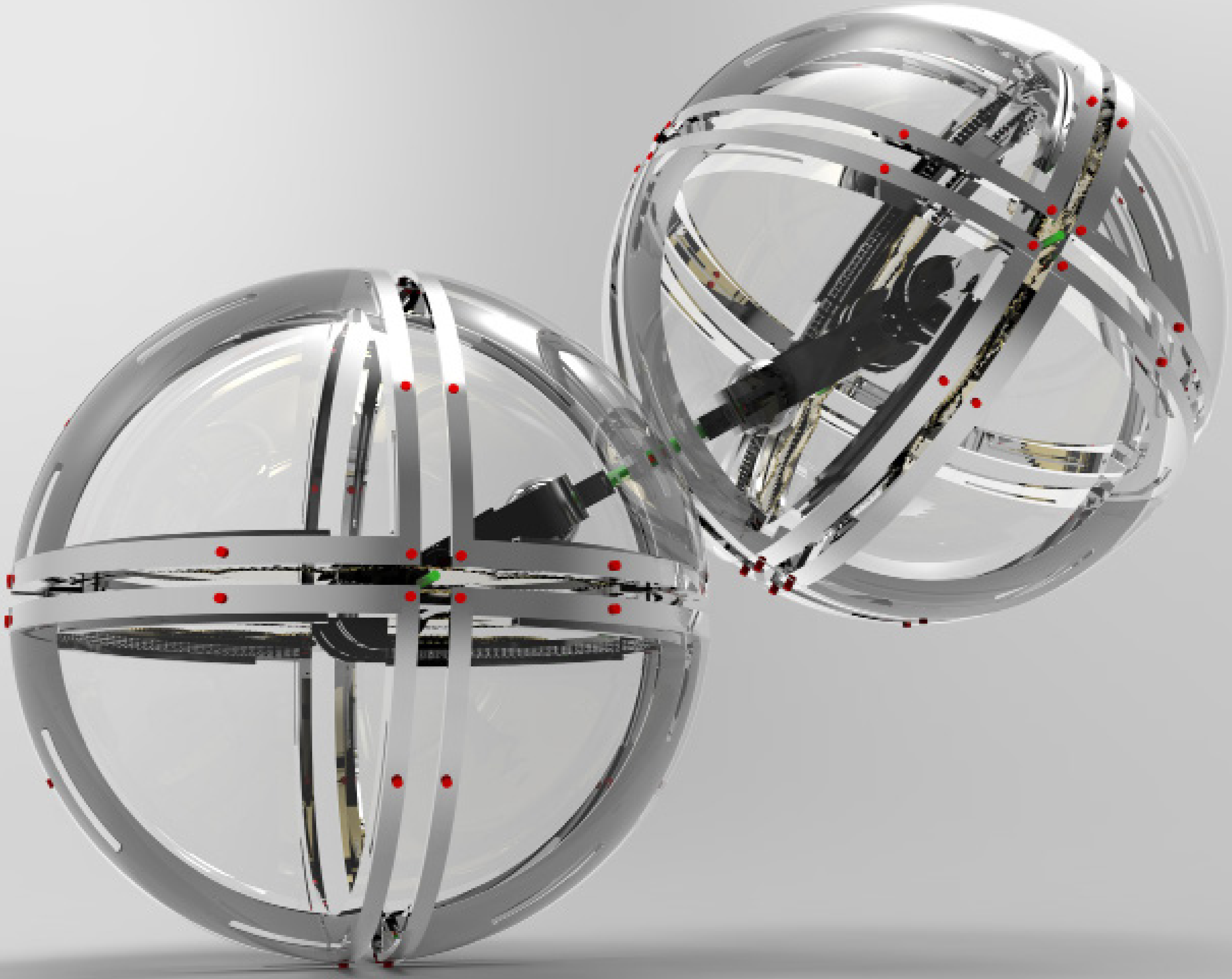
DESIGN FOR SELF- ASSEMBLY



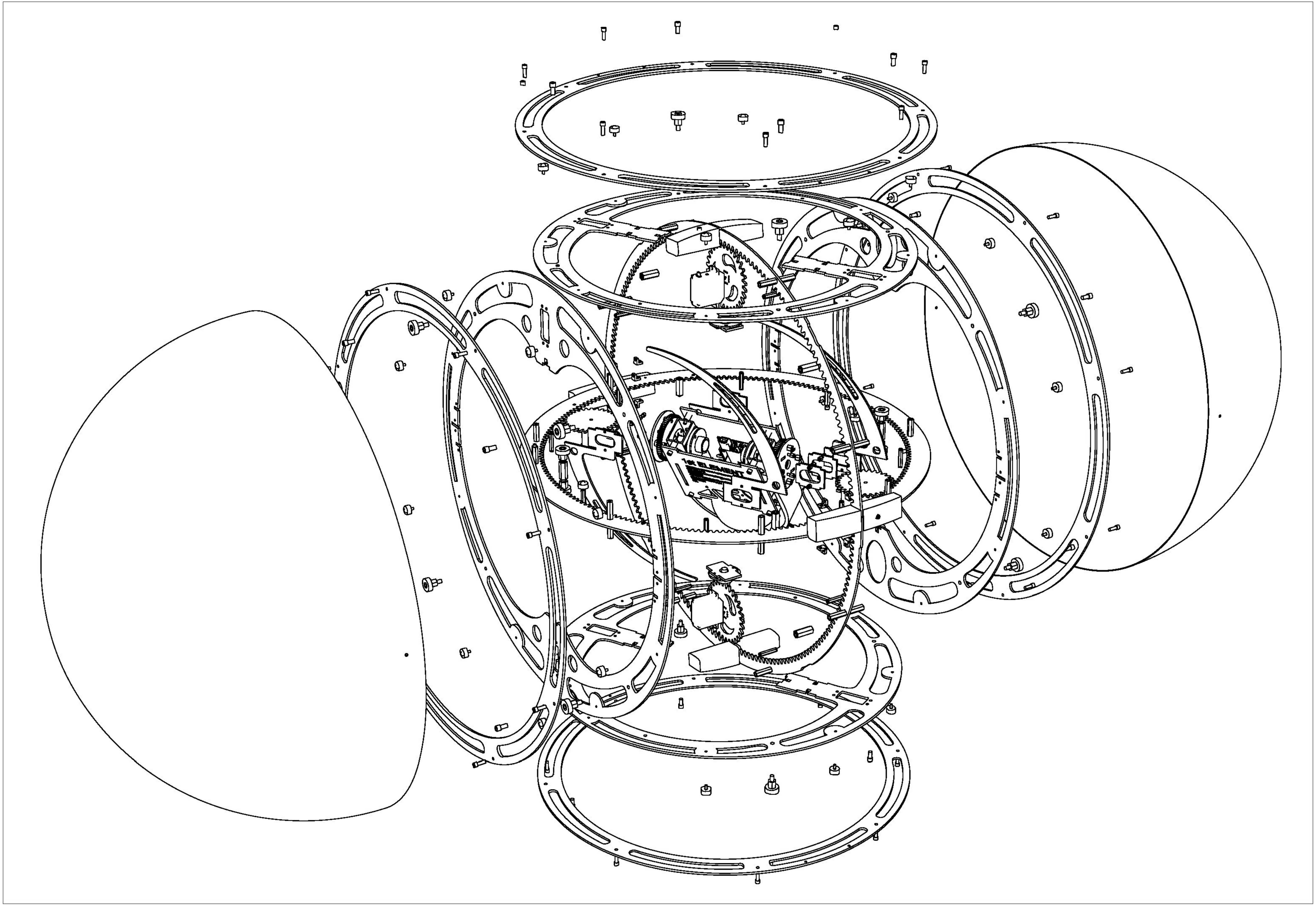
rotation1



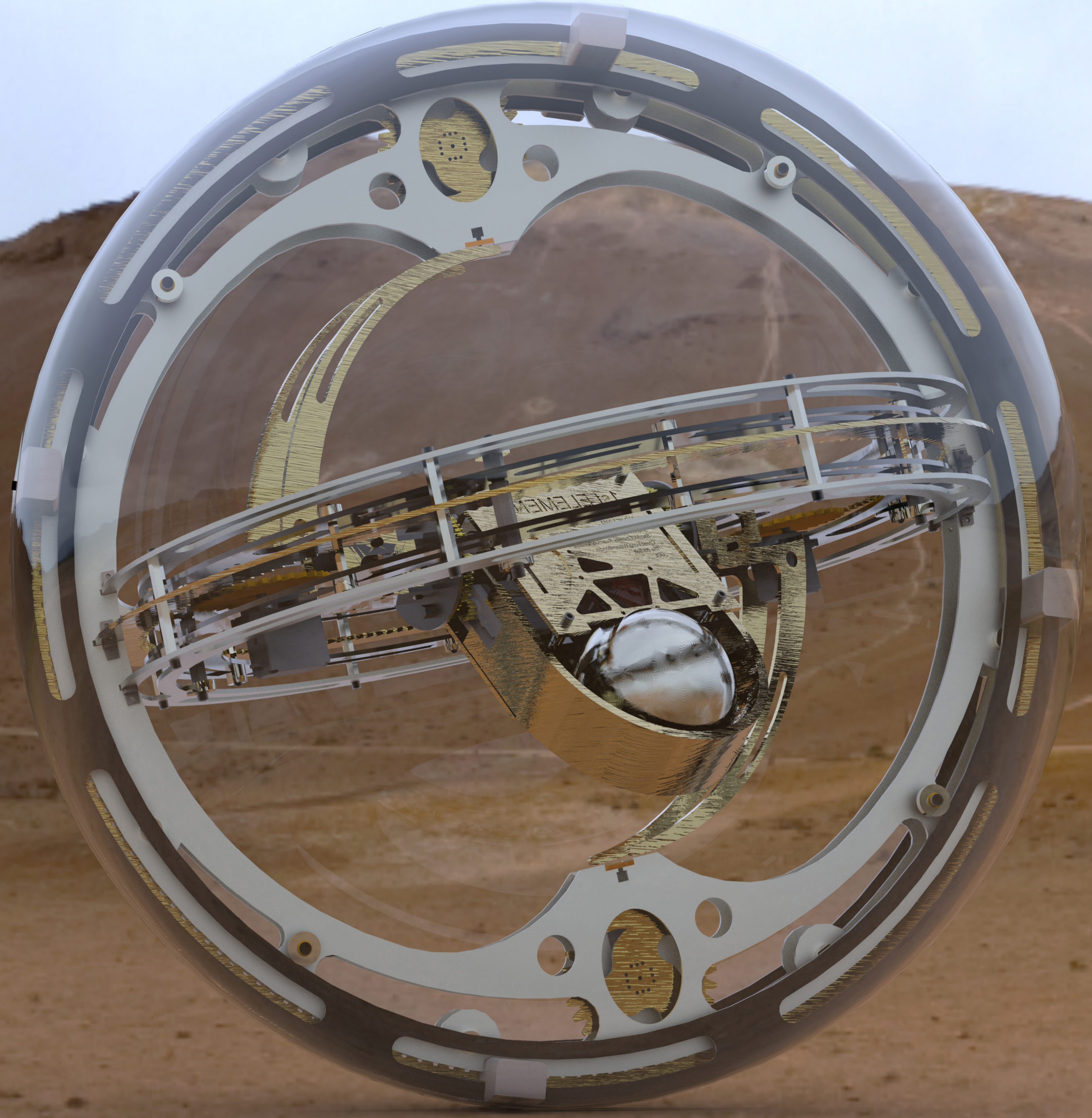
rotation2



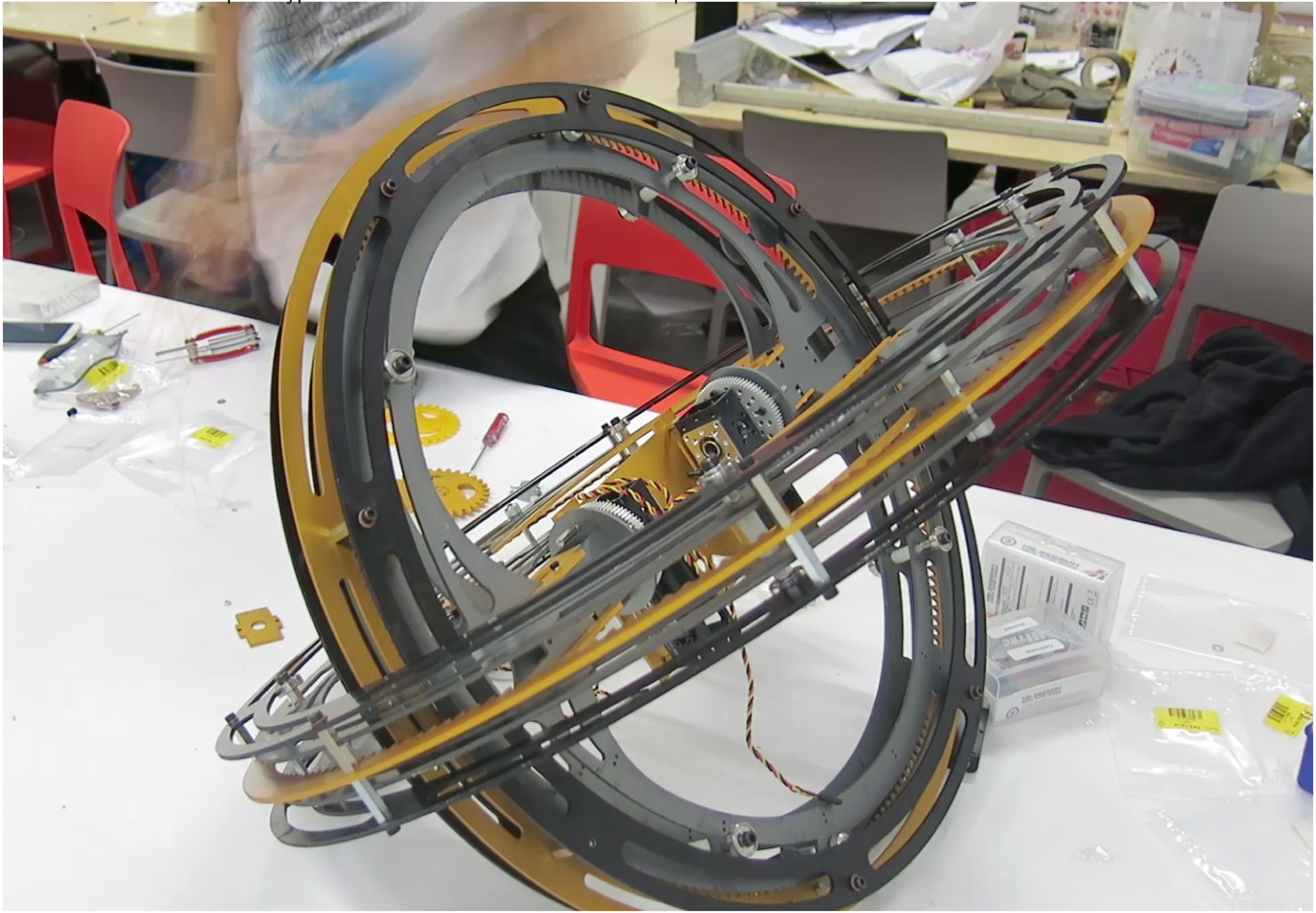
DESIGN FOR 3 AXIS MODEL



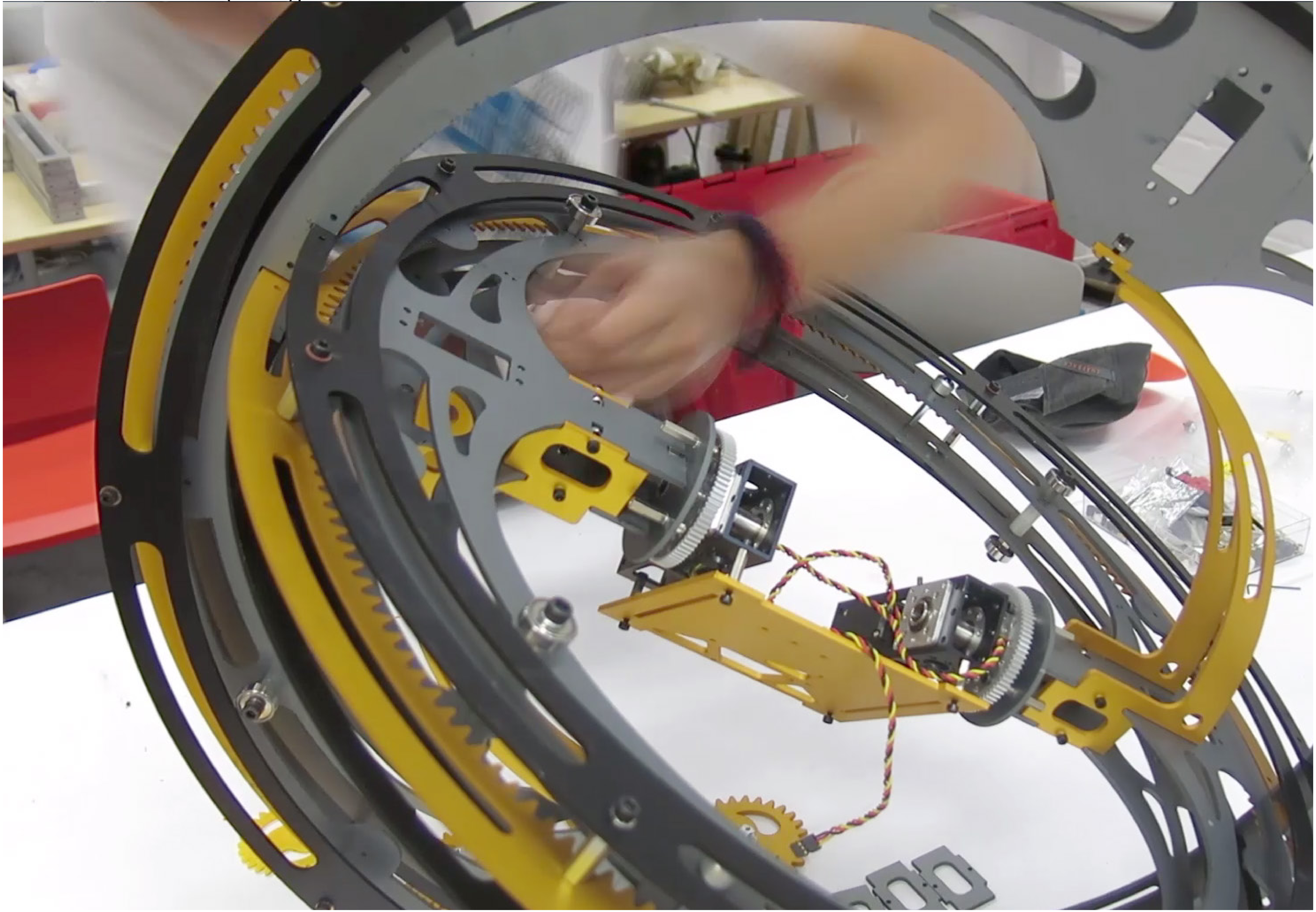
3 AXIS SPHERE ROBOT， WOULD BE BUILT IN 2 WEEKS



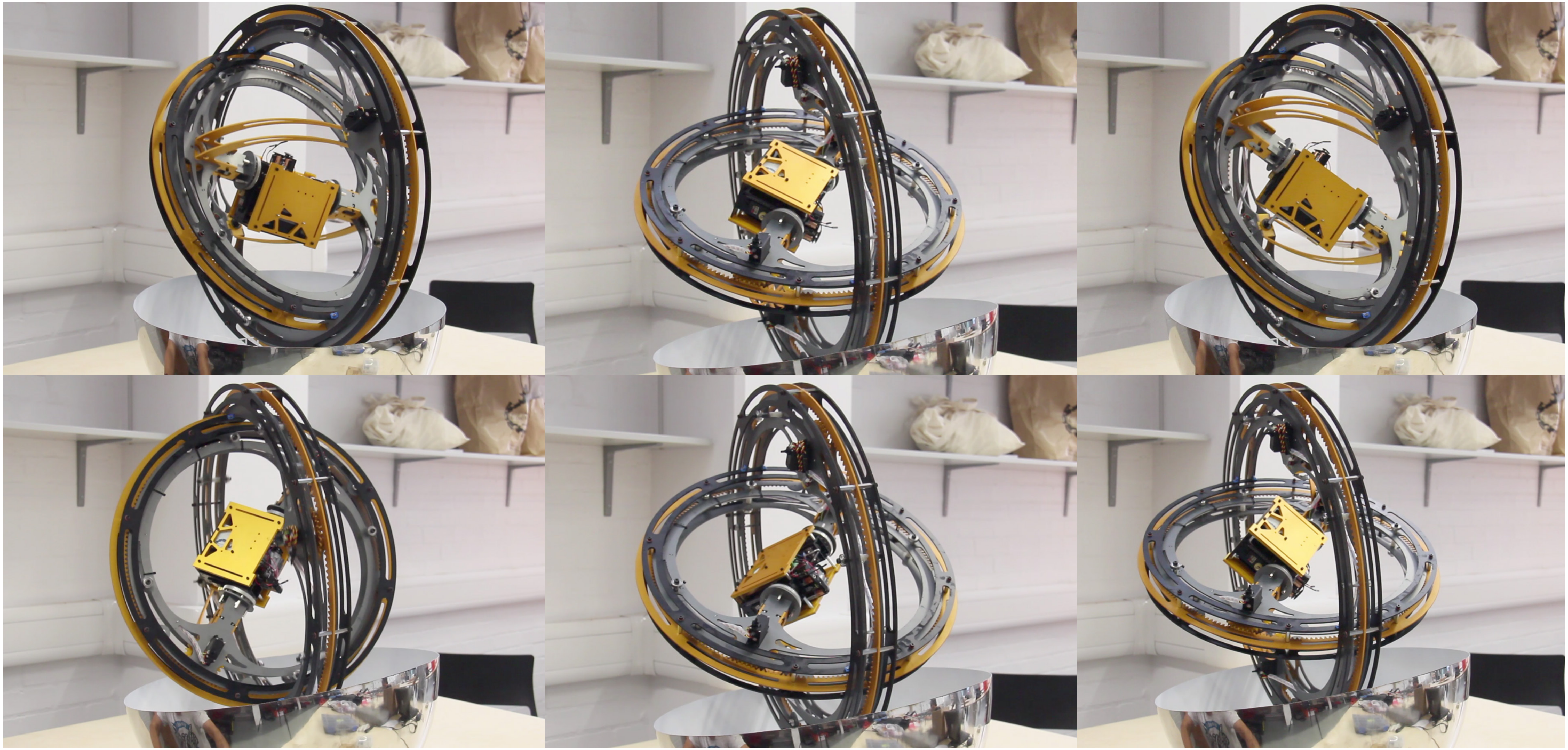
Fabrication of the 6th prototype of “1st Element” . more than 700 parts inside it.



Fabrication of the 6th prototype of “1st Element” .

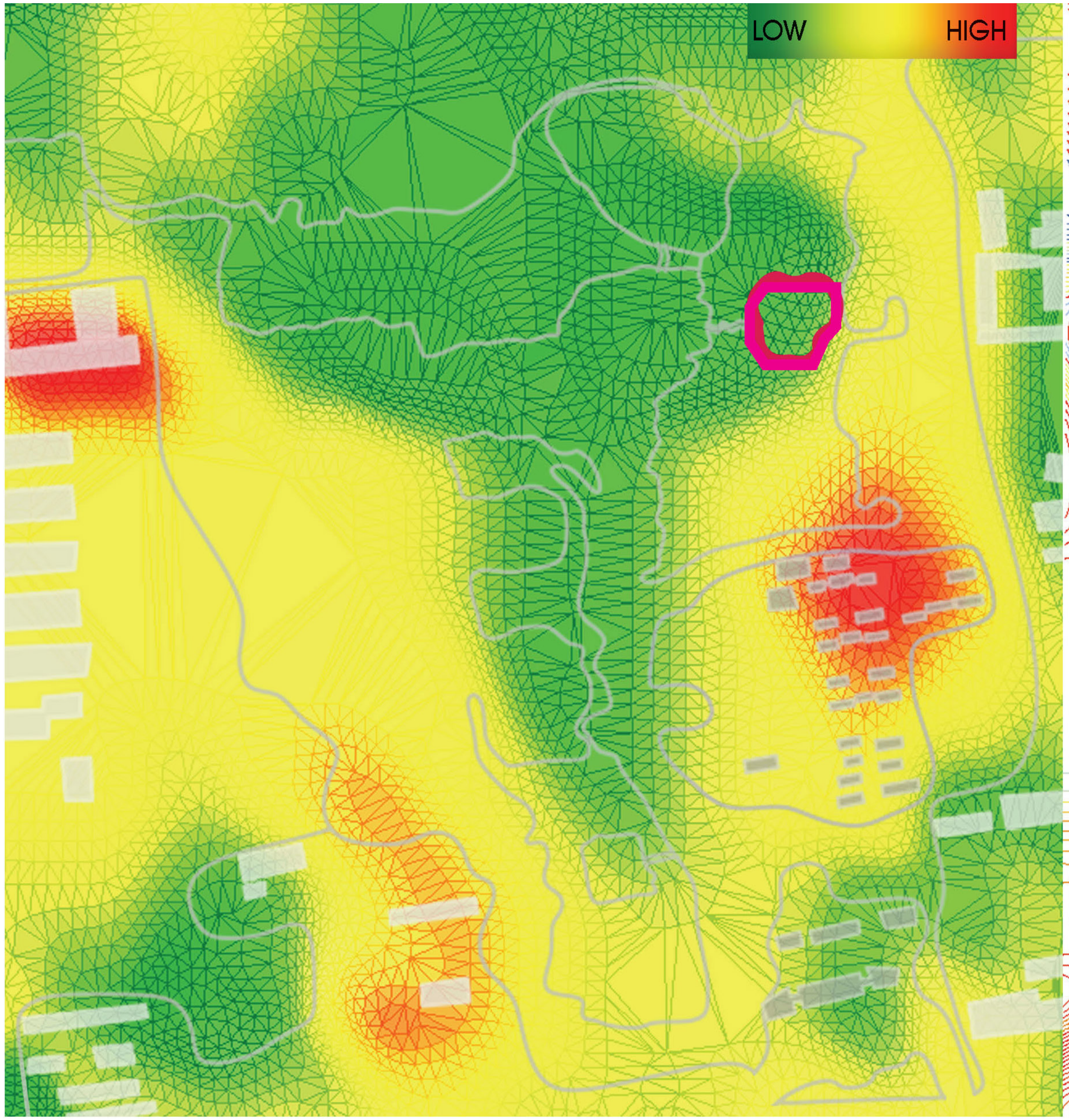


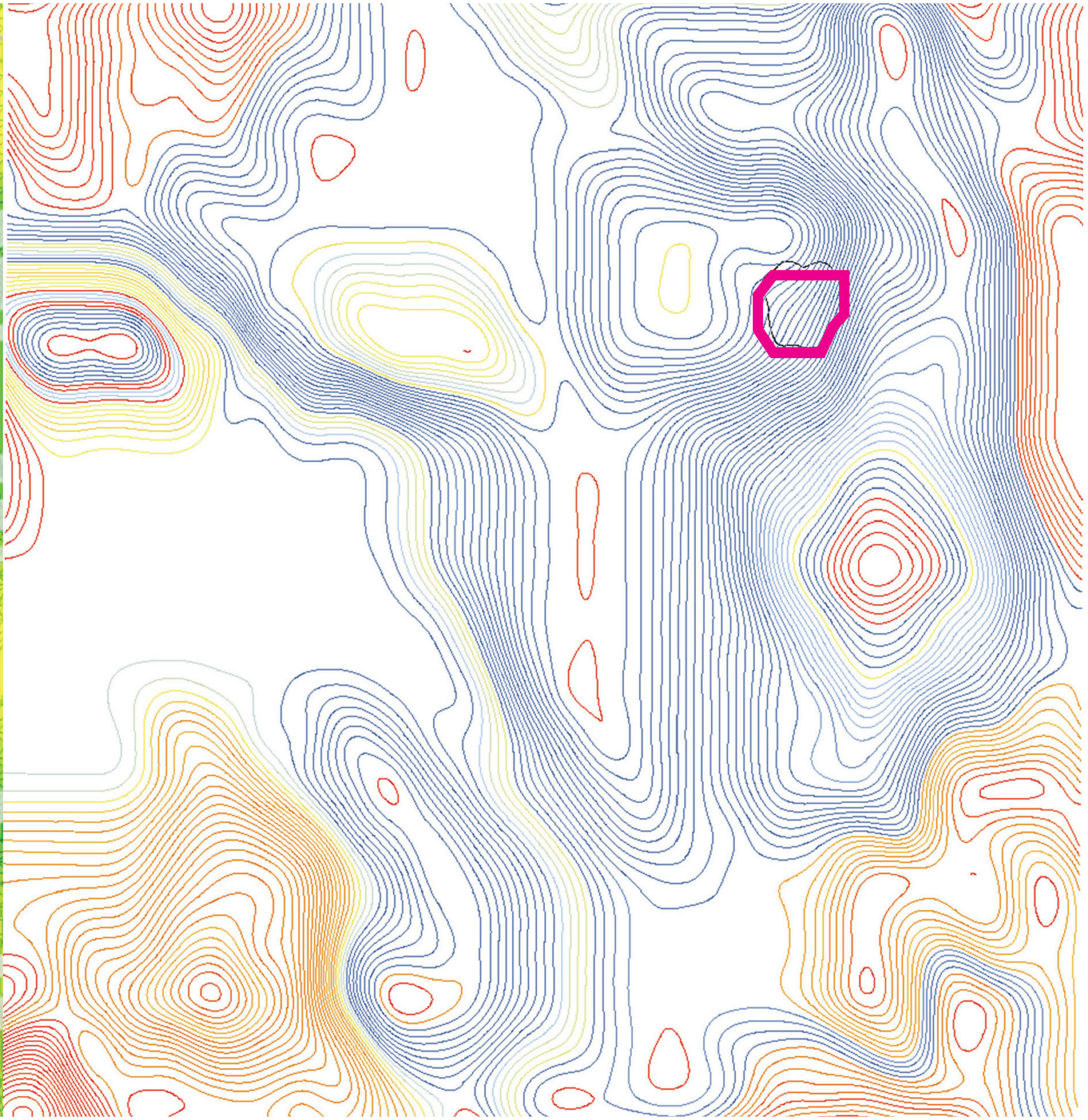
First 3-axises movement been captured in classroom



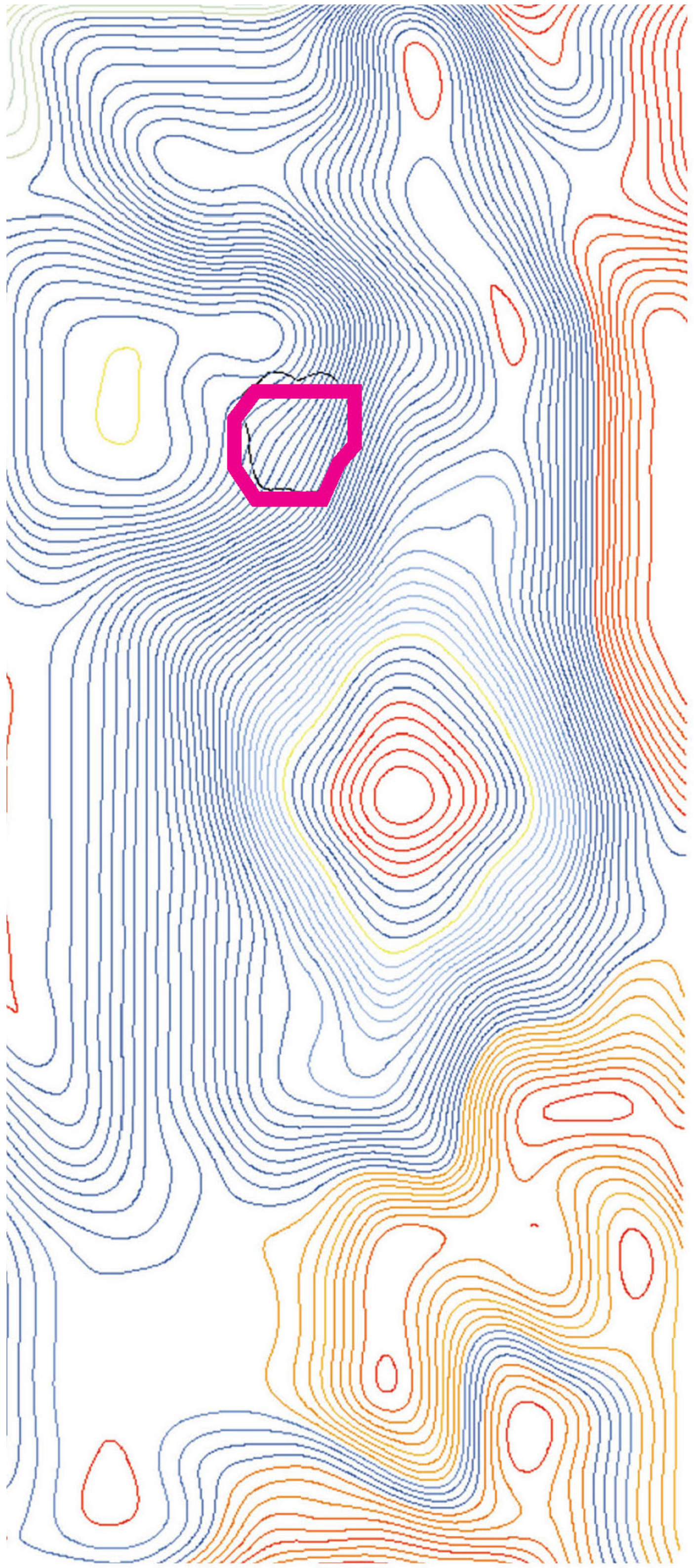
Computational Design Research

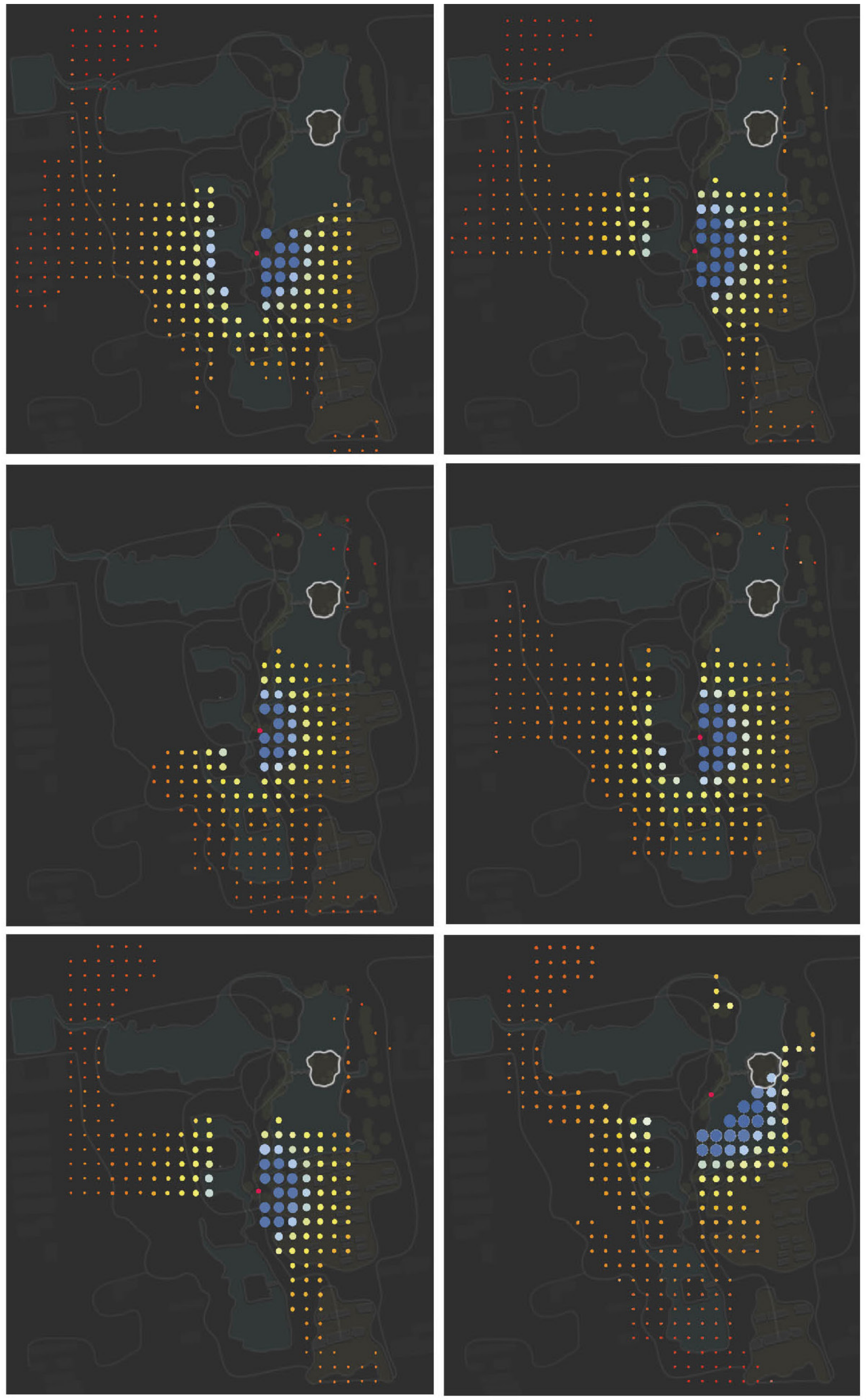
Comptutational research in Beijing

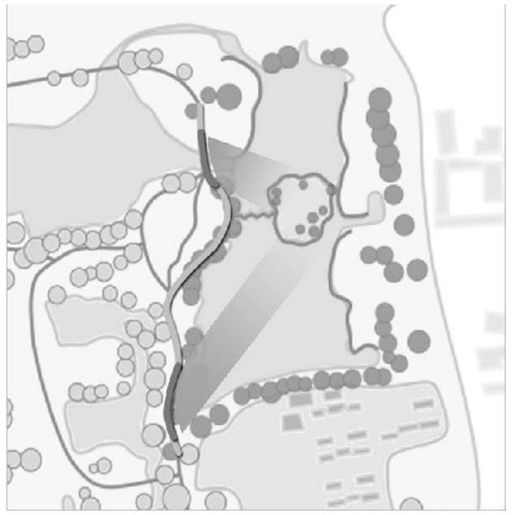




Site







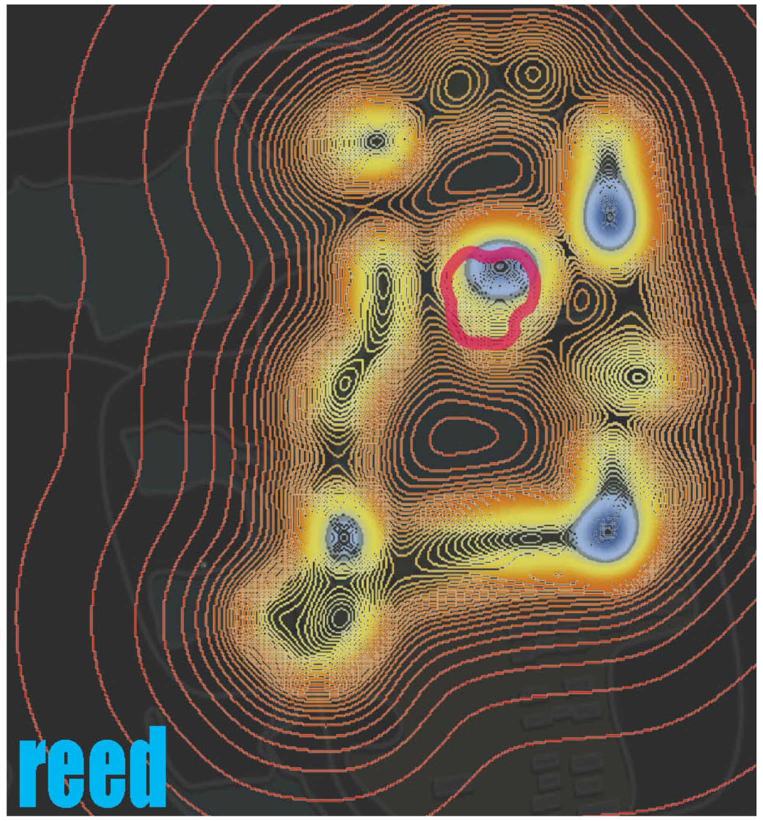
▬ surrounding road
▬ sections of good line of sight
▨ area can have good view of the island

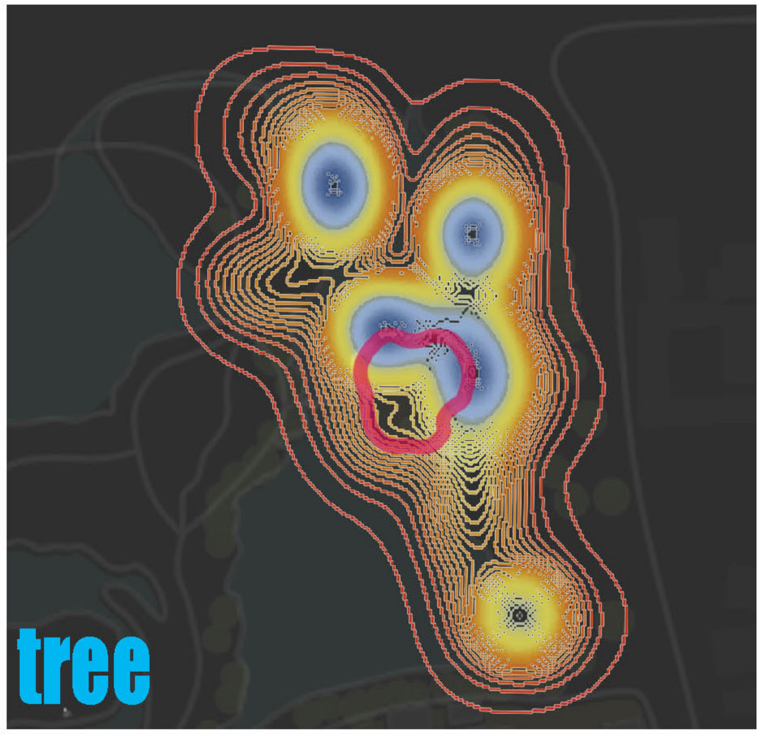
clear
vague

CLARITY
(from the round to the island)

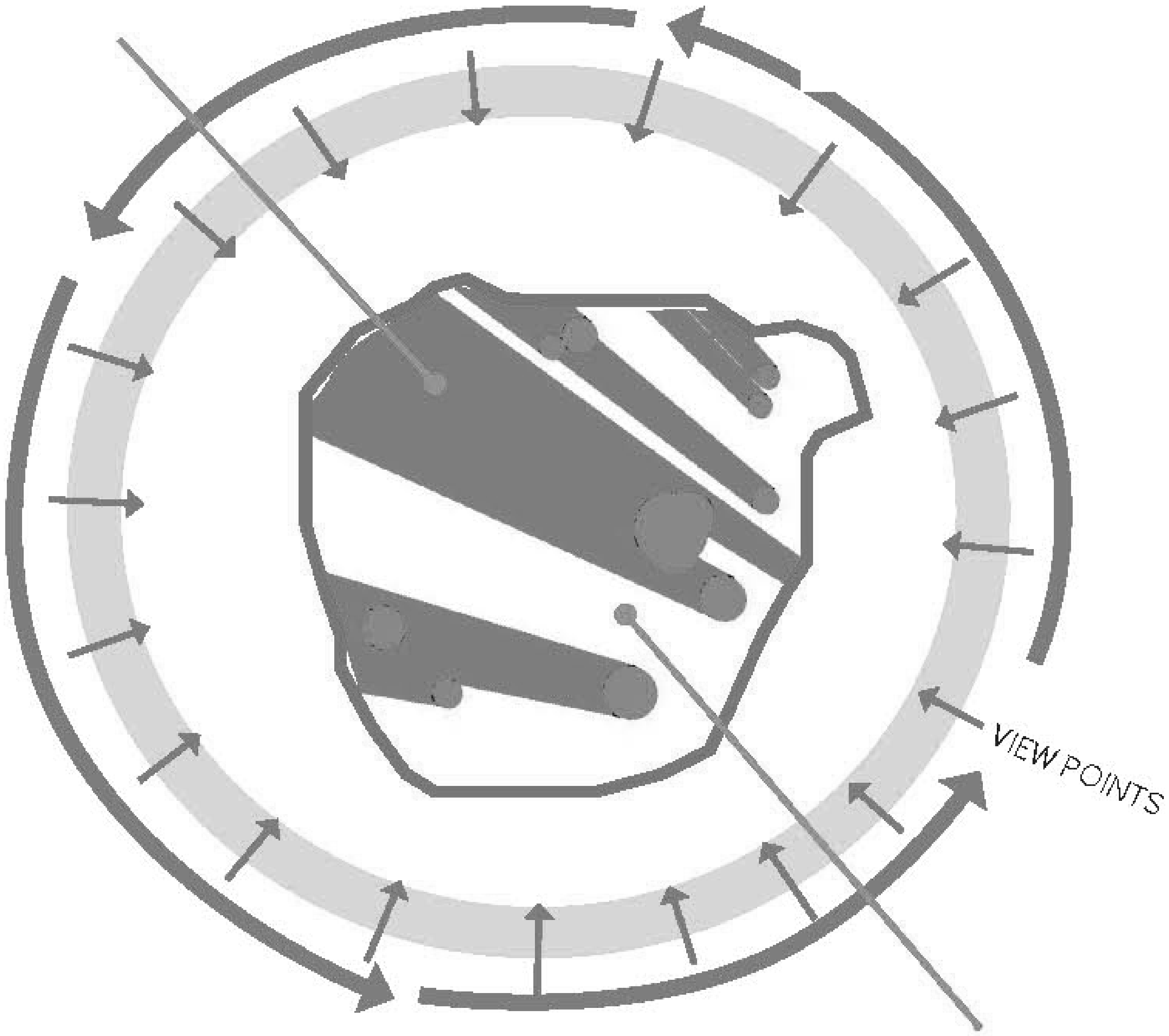
view

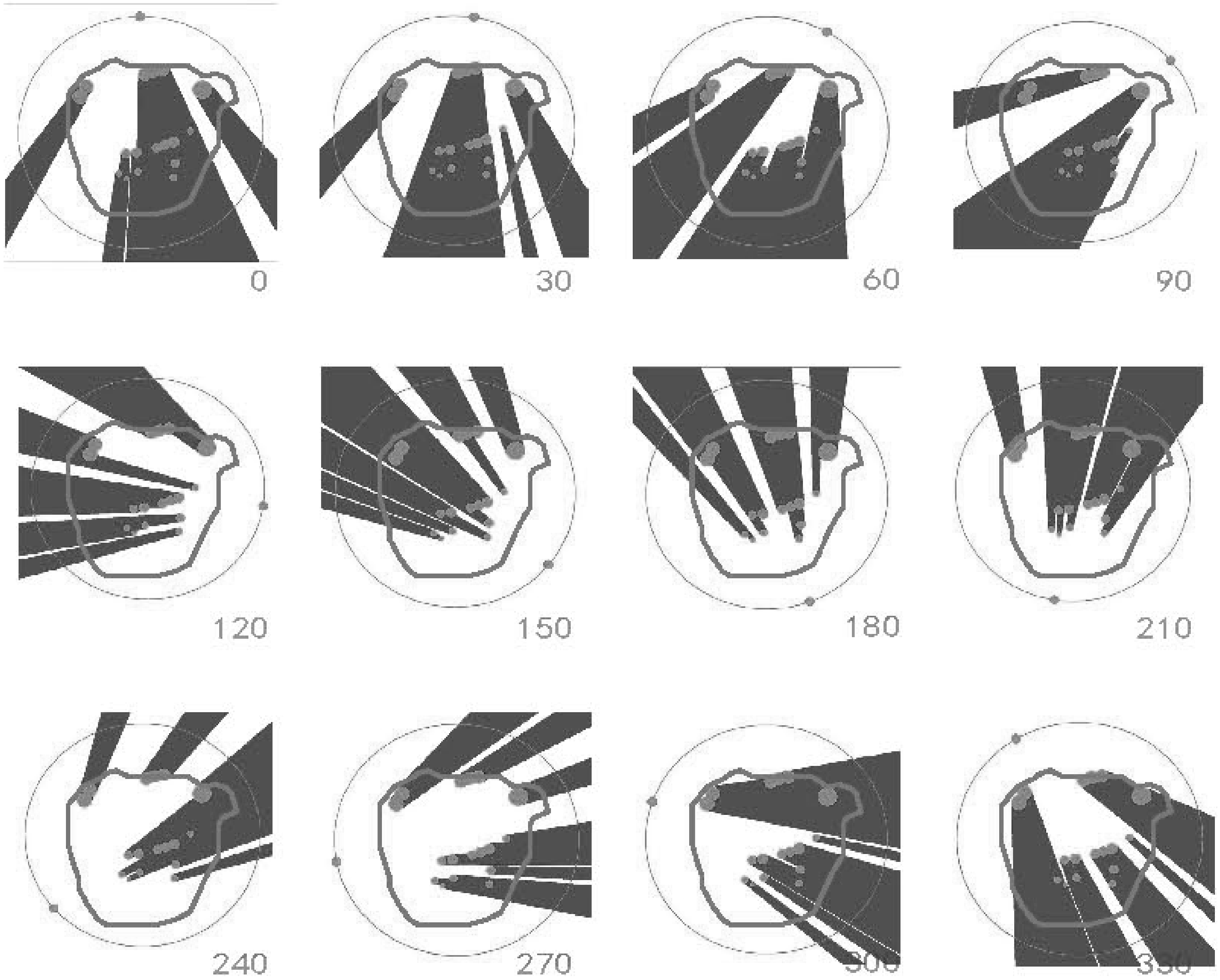
we analyse the view ,the surrounding trees,reeds which impect in the site. we expect to find some interesting things.



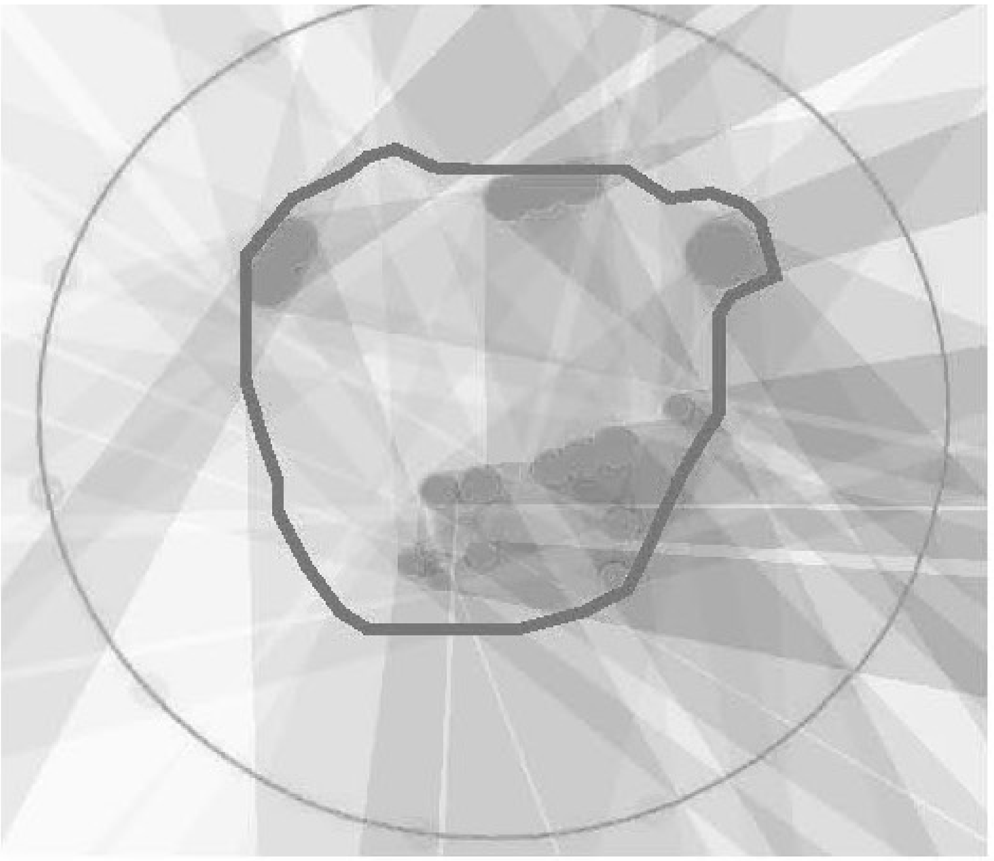


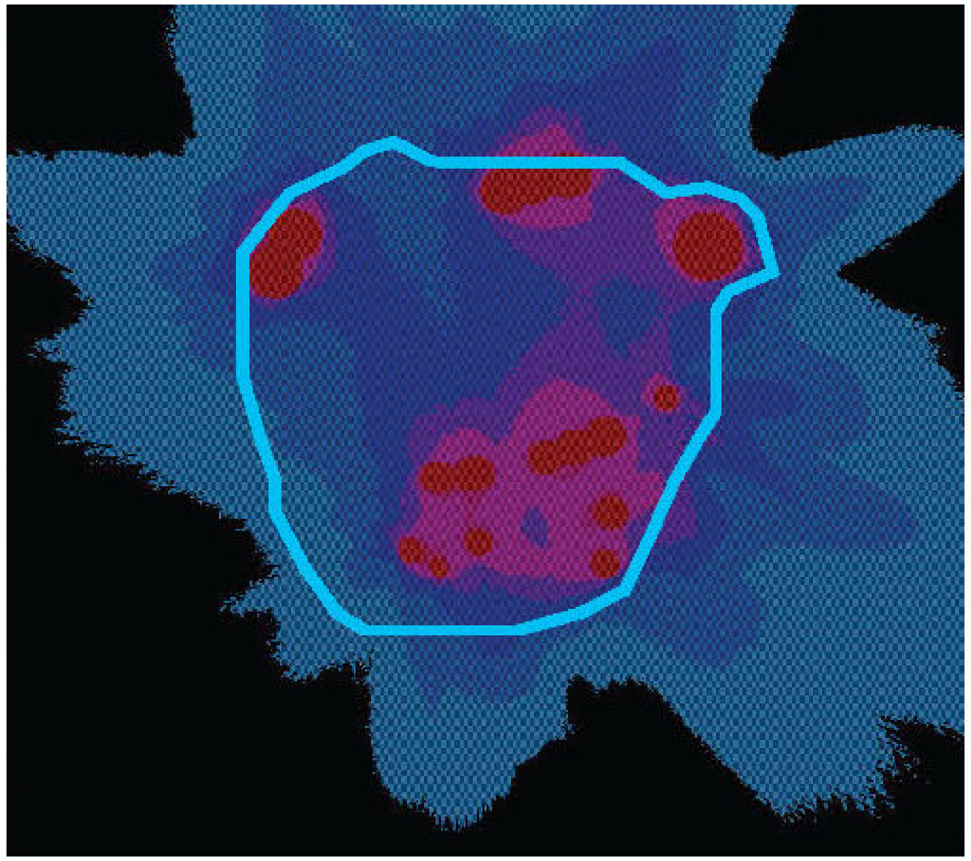
Vision analyze by Processing

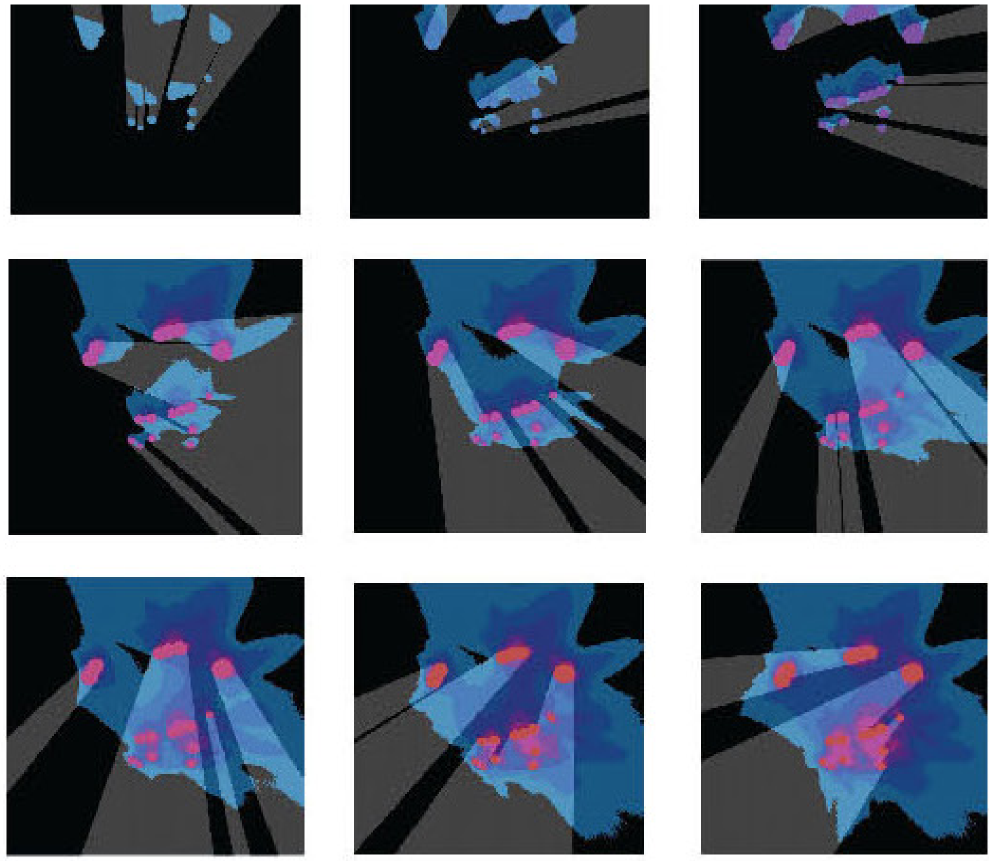




Vision analyze by Processing







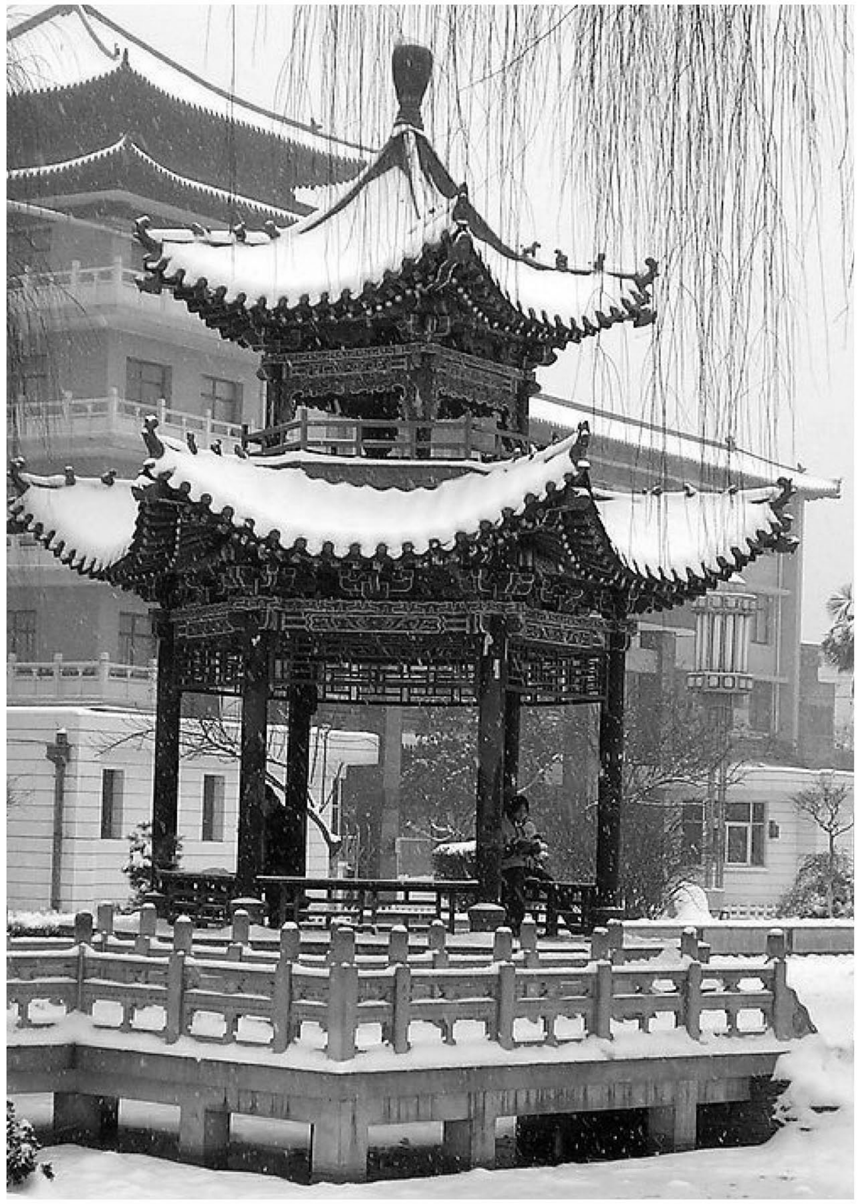
it is difficult to find what is happened in the site ,so I change my code in proceesing to use different color to repesent the ability of each point in the site to having the view of the lake outside

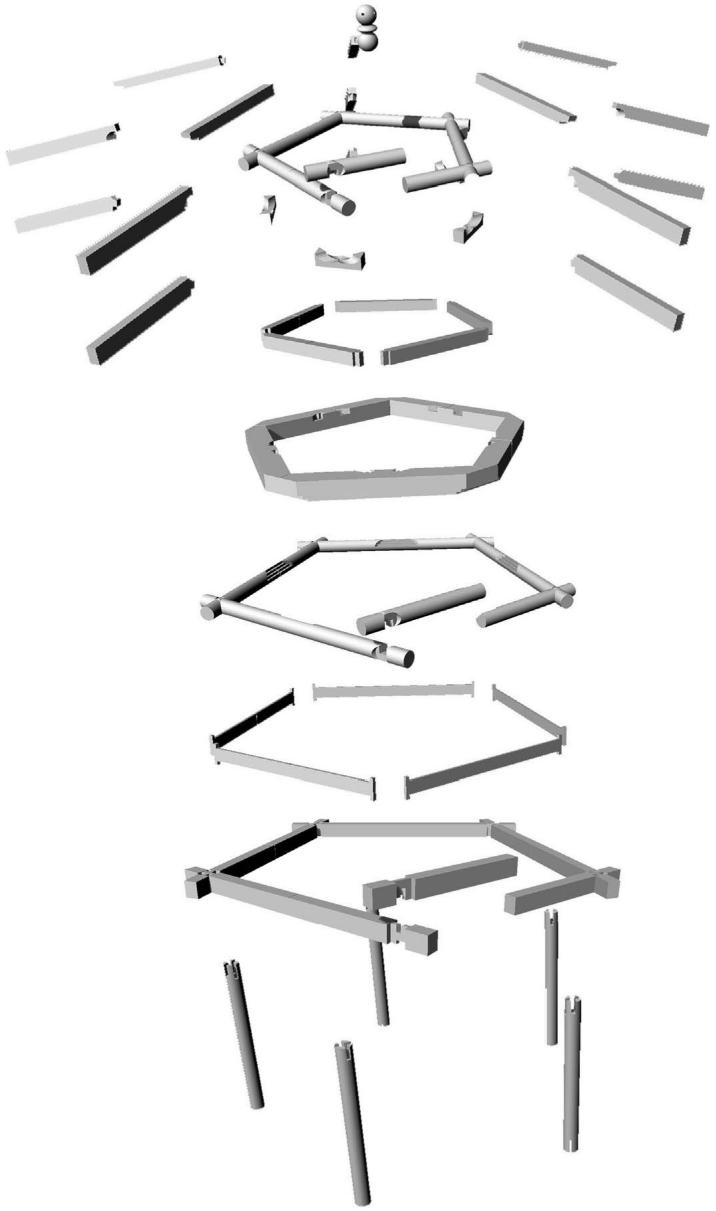
ability of view

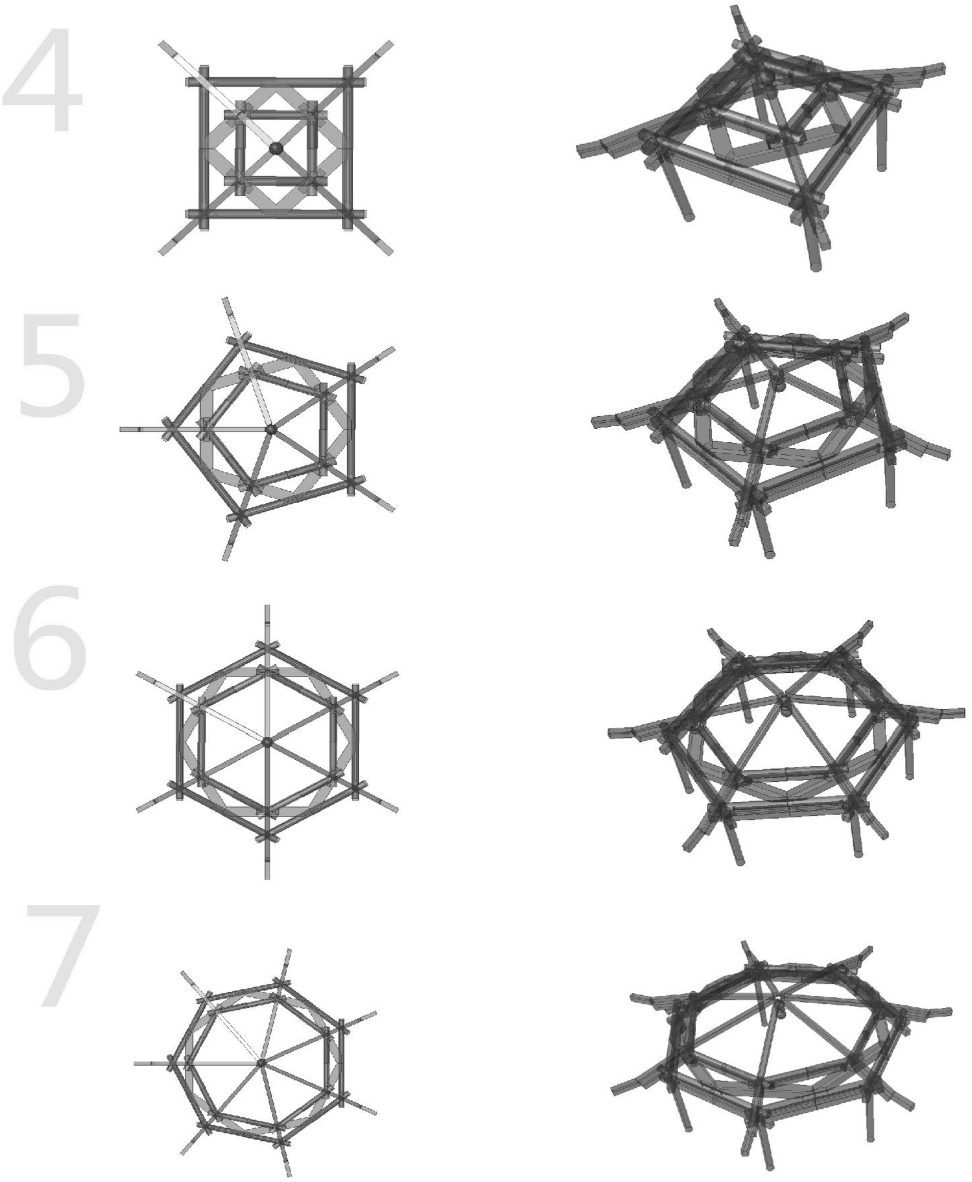
🟥	60-85	of 360
🟪	85-110	of 360
🟪	110-160	of 360
🟪	160-185	of 360
🟦	185-210	of 360
🟦	210-235	of 360
🟦	235-260	of 360

```
 if (CenterZ[m][n]  >=  275   &&  CenterZ[m][n]<300)
{fill(180,18,94);}
  if (CenterZ[m][n]  >=  250   &&  CenterZ[m][n]<275)
{fill(180,18,125);}
 if (CenterZ[m][n]  >=  200   &&  CenterZ[m][n]<250)
{fill(180,18,159);}
  if (CenterZ[m][n]  >=  175   &&  CenterZ[m][n]<200)
{fill(102,18,180);}
  if (CenterZ[m][n]  >=  150   &&  CenterZ[m][n]<175)
{fill(18,60,180);}
   if (CenterZ[m][n] >=  125   &&  CenterZ[m][n]<150)
{fill(18,90,180);}
 if (CenterZ[m][n]  >=  100   &&  CenterZ[m][n]<125)
{fill(18,119,180);}
```

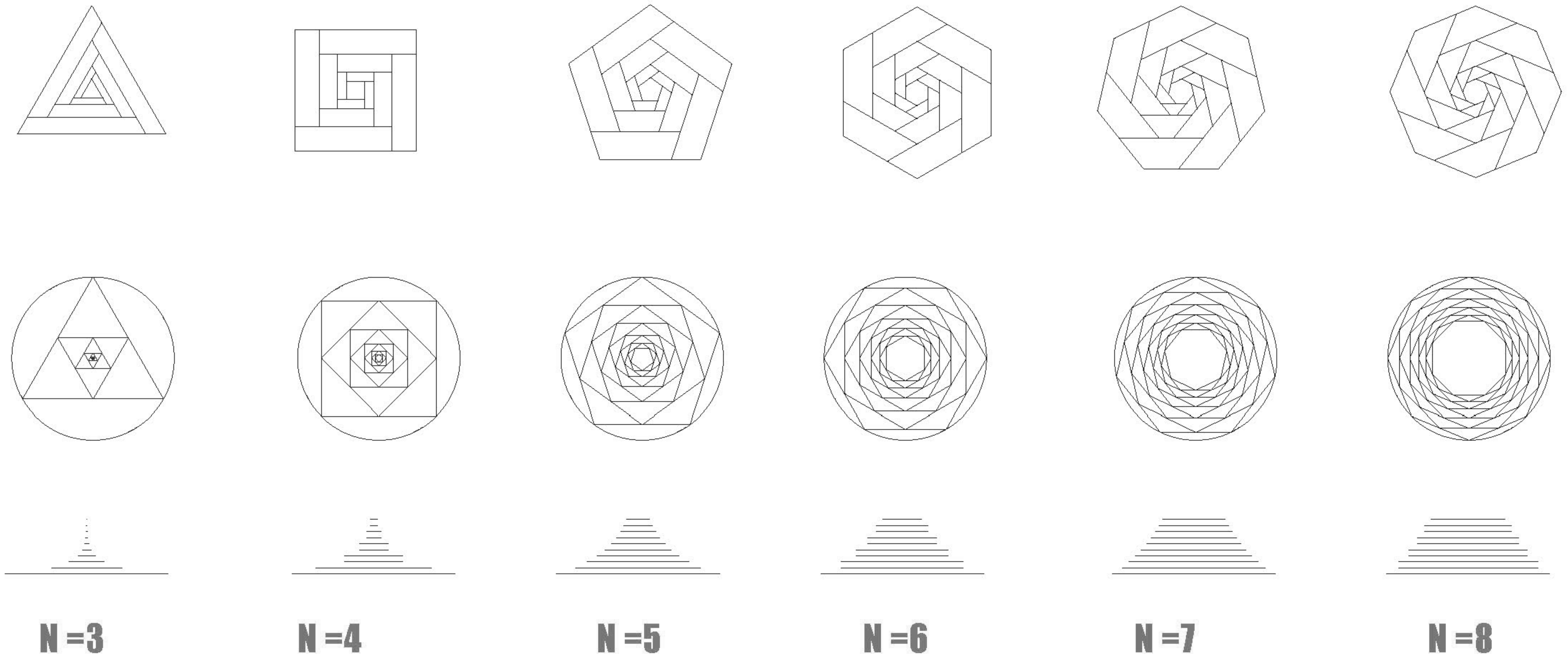
Reconstruction of the traditional booth by Grasshopper



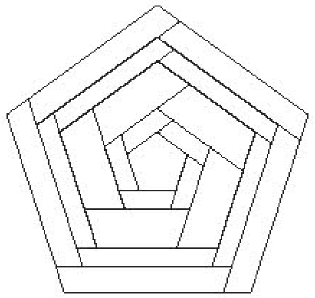


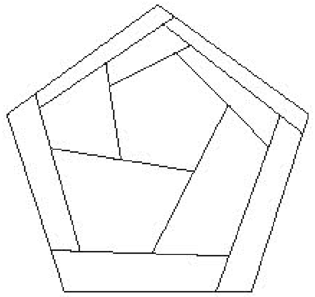


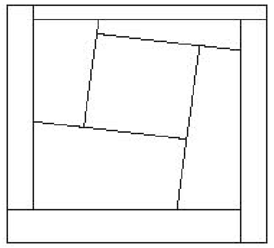
Development of the traditional method of fabrication of the wood beam.

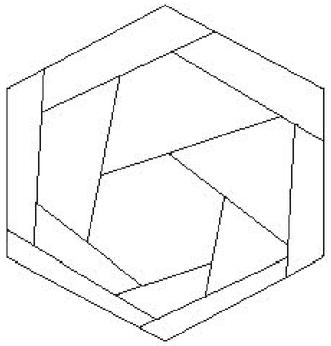


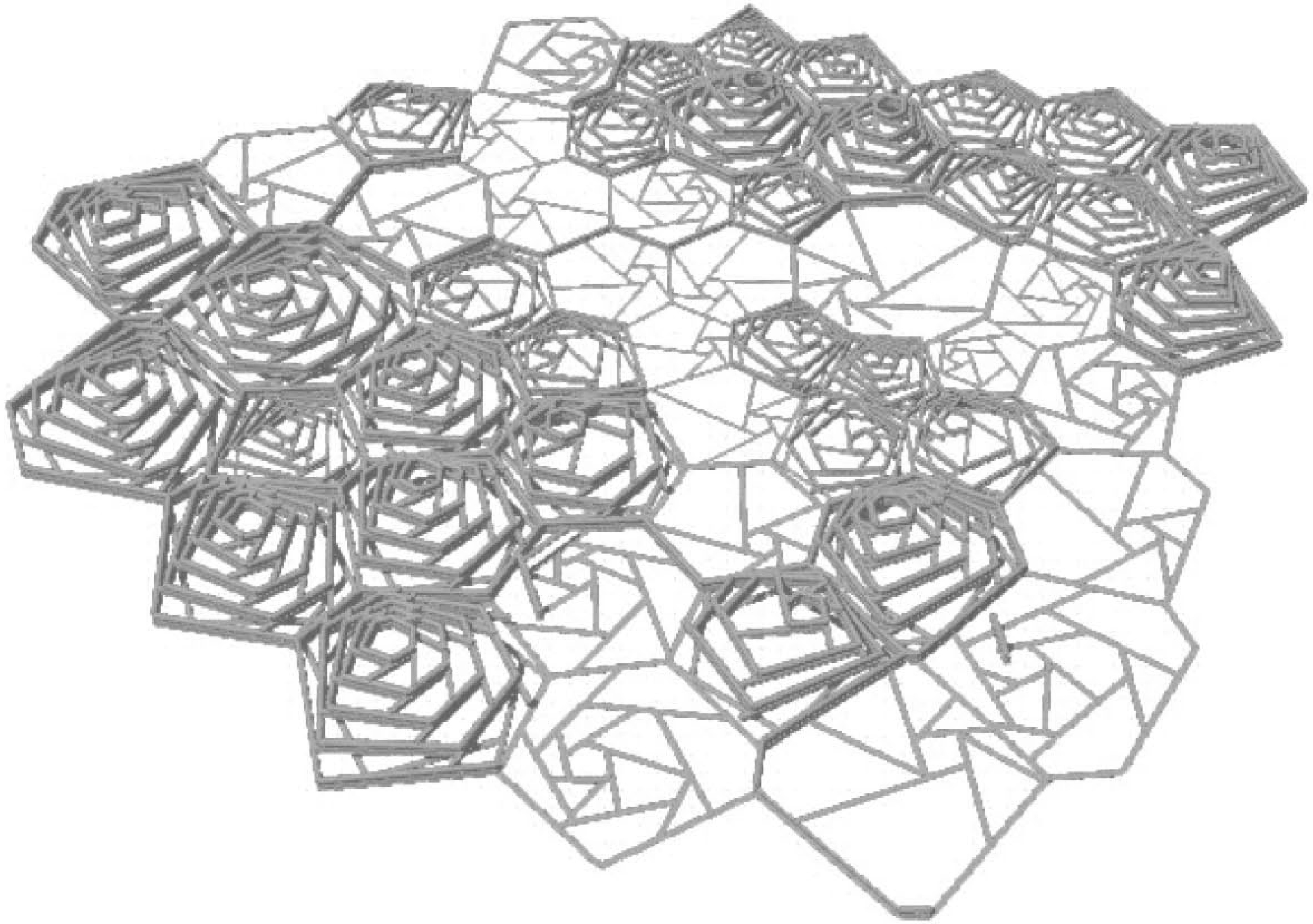
Estabiish a relationship betewwn envirnment and constuction of the basic element



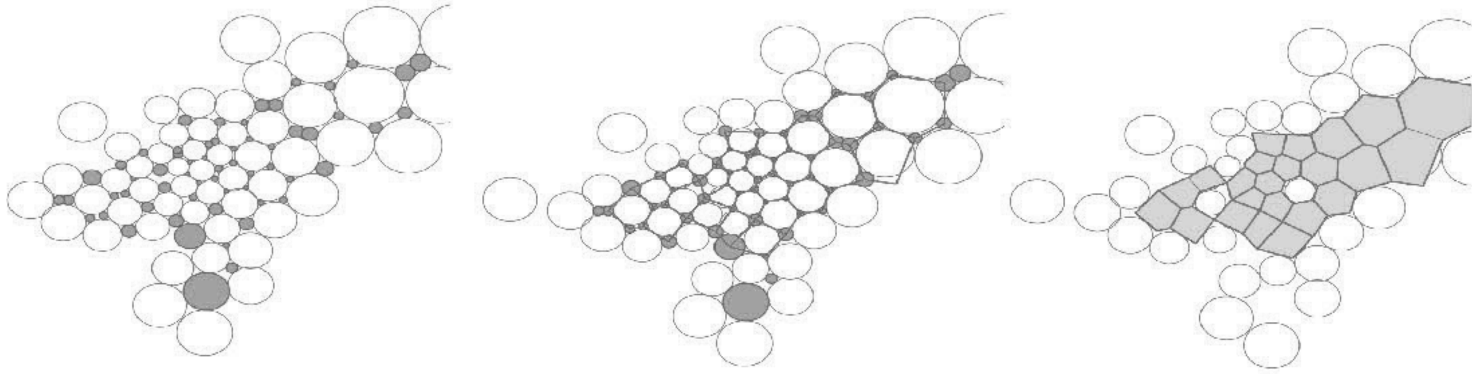


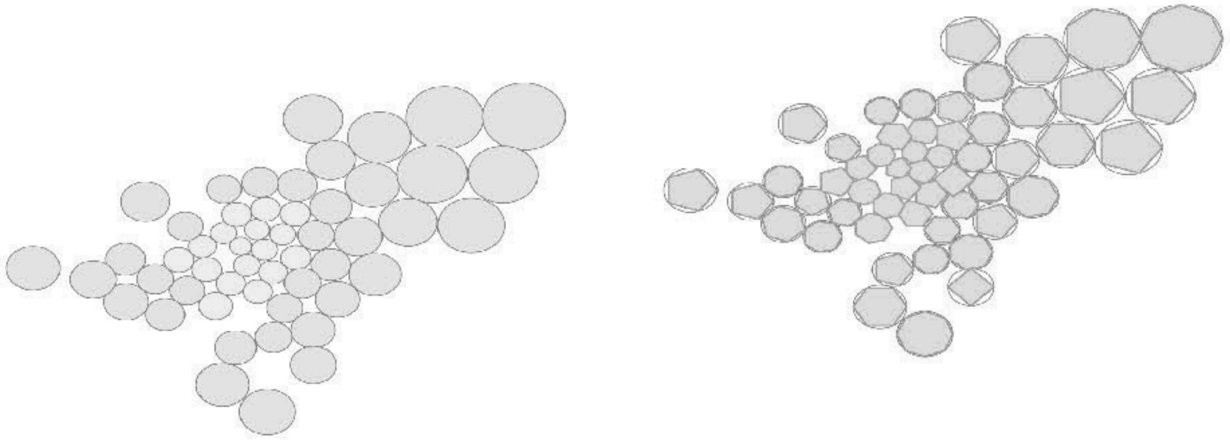


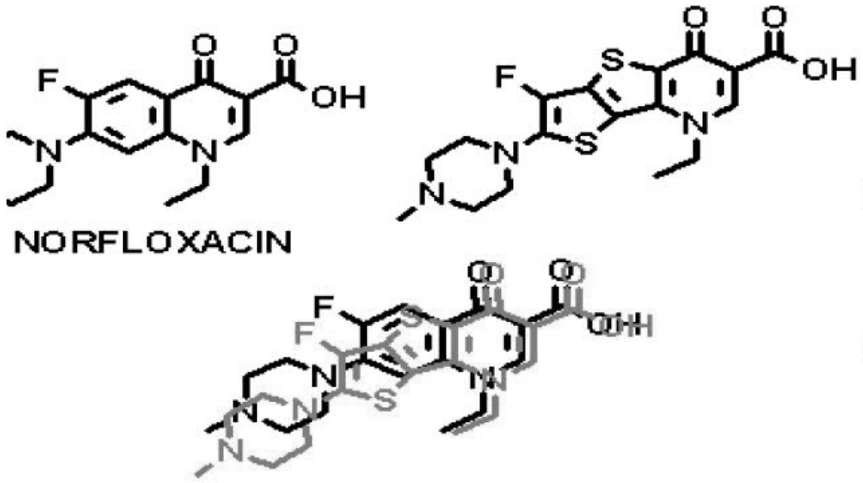




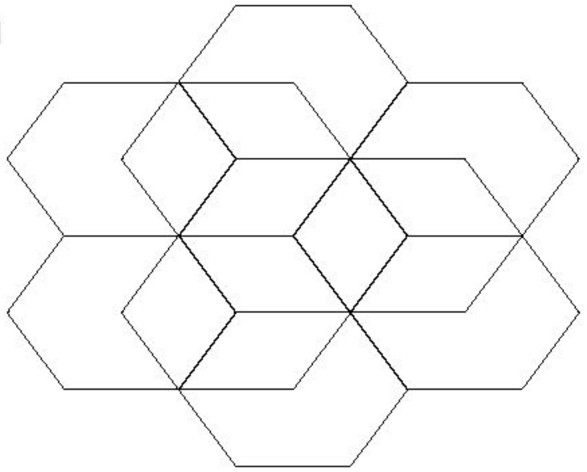
Applying the circle packing system to define the site.

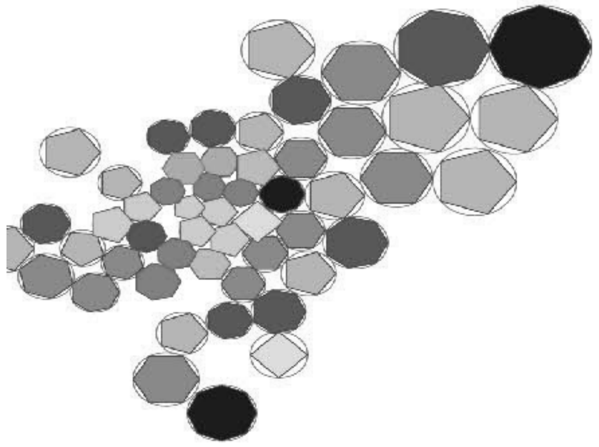


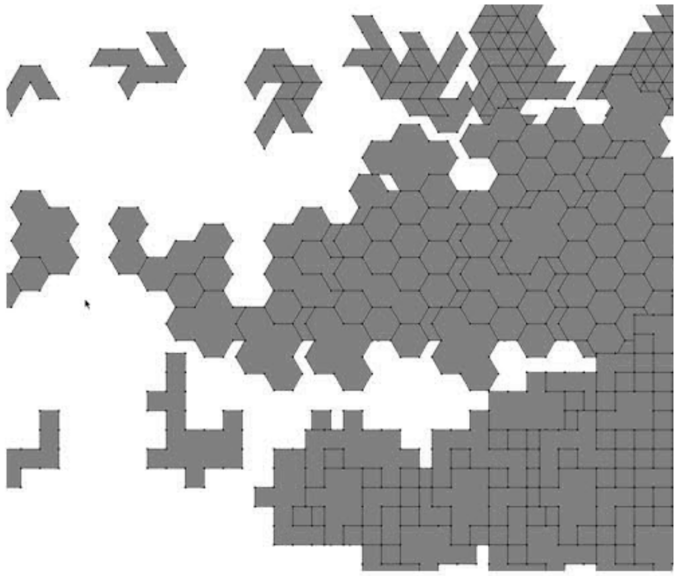




NORFLOXACIN

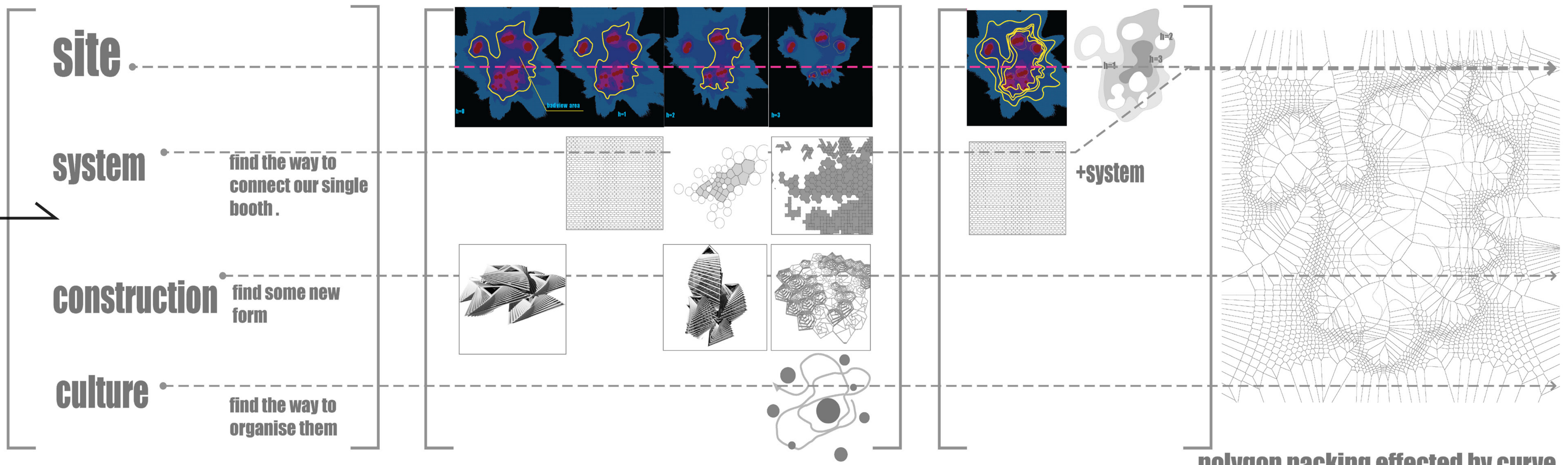






Combine of the design, culture, site, environment and structure..

**we need to enhance the feel of the space,
keep people stay here .
we find the relationship between the view
and the abilty to keep people here.**



site

system

find the way to connect our single booth .

construction

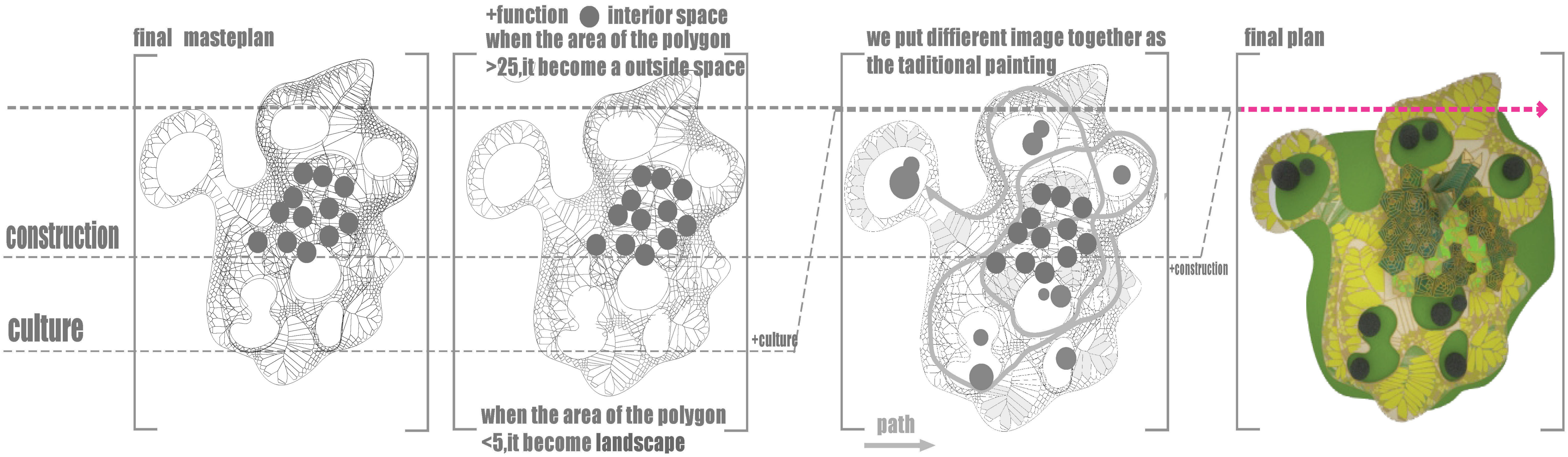
find some new form

culture

find the way to organise them

+system

polygon packing effected by curve



final masteplan

construction

culture

**+function ● interior space
when the area of the polygon >25,it become a outside space**

when the area of the polygon <5,it become landscape

+culture

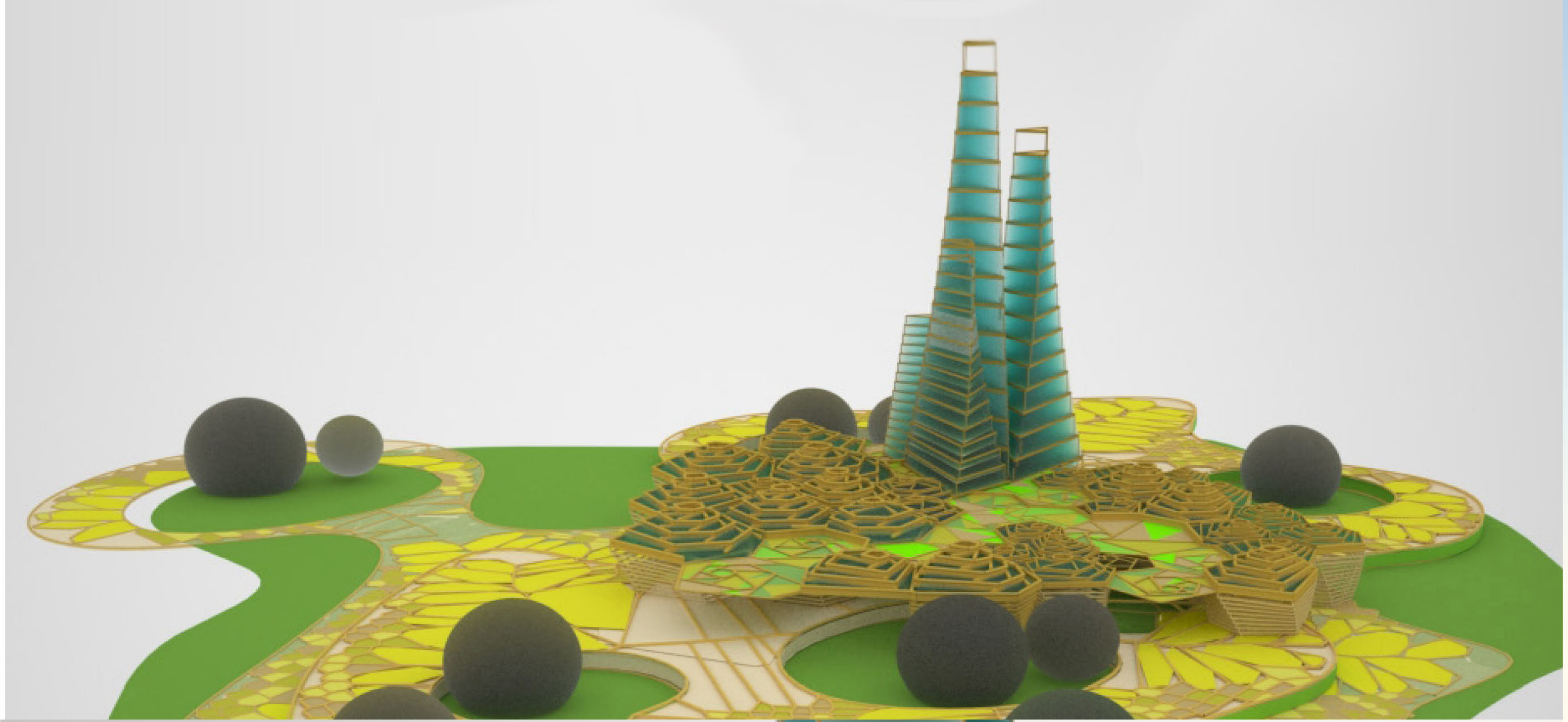
we put diffierent image together as the taditional painting

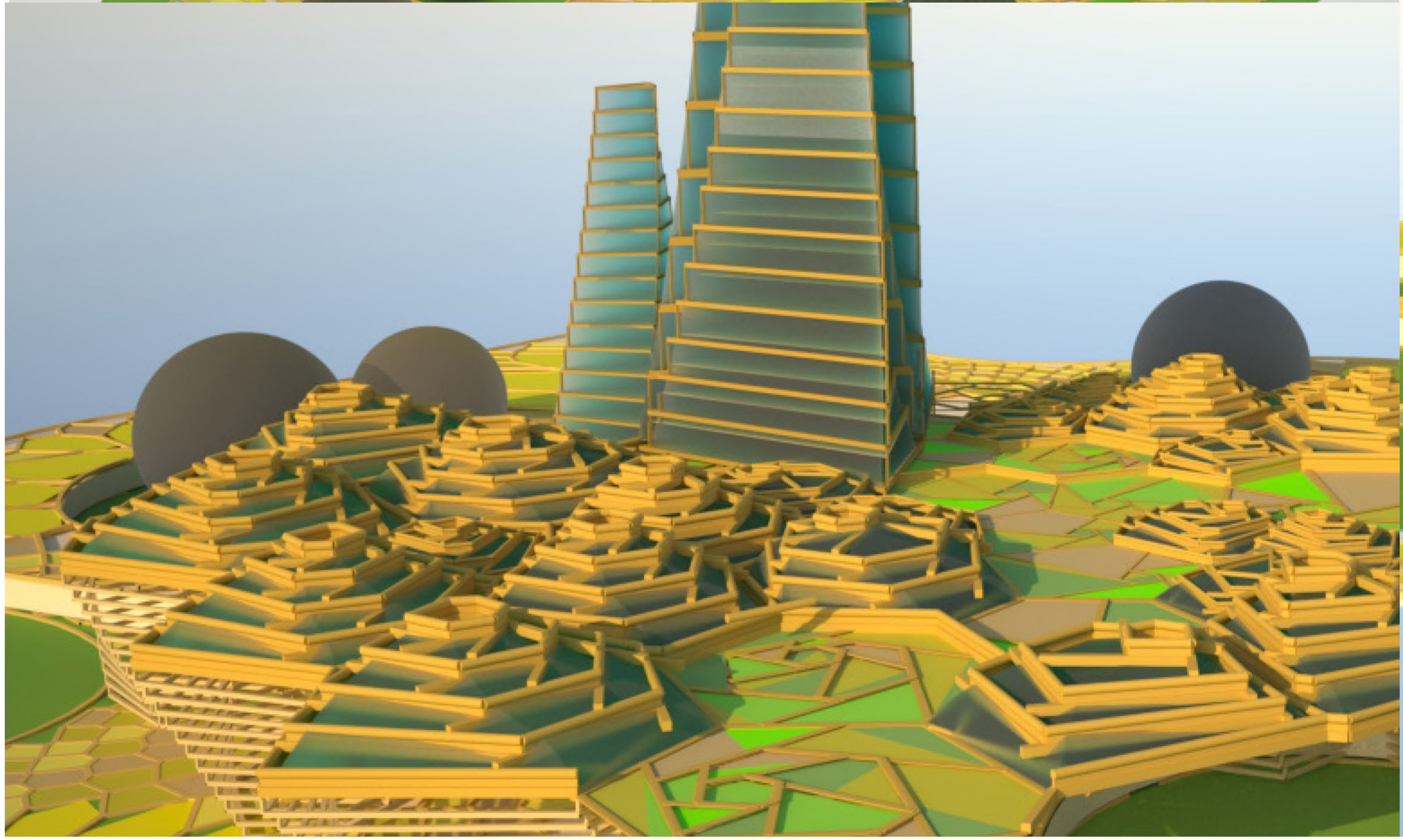
path

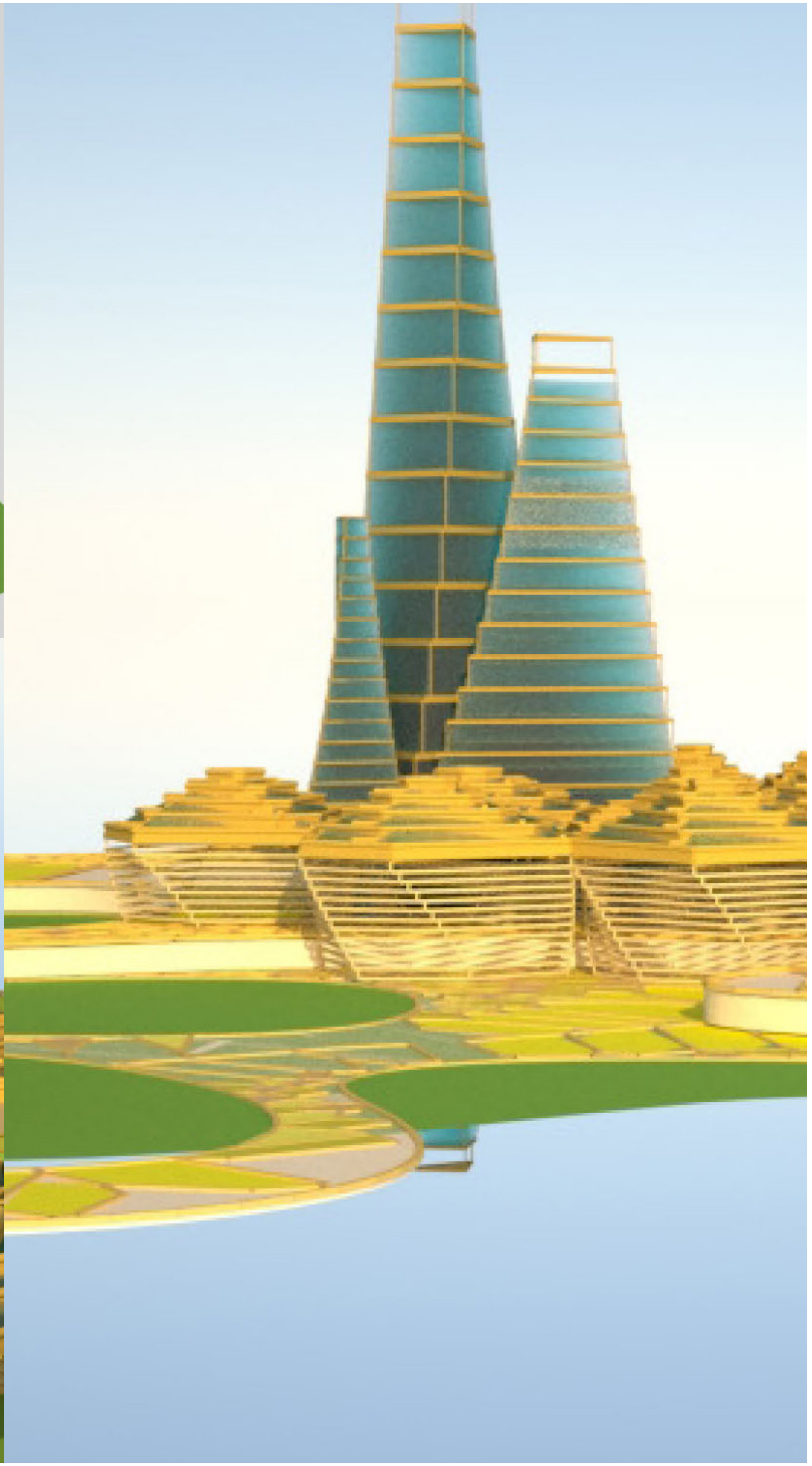
+construction

final plan

Rendering

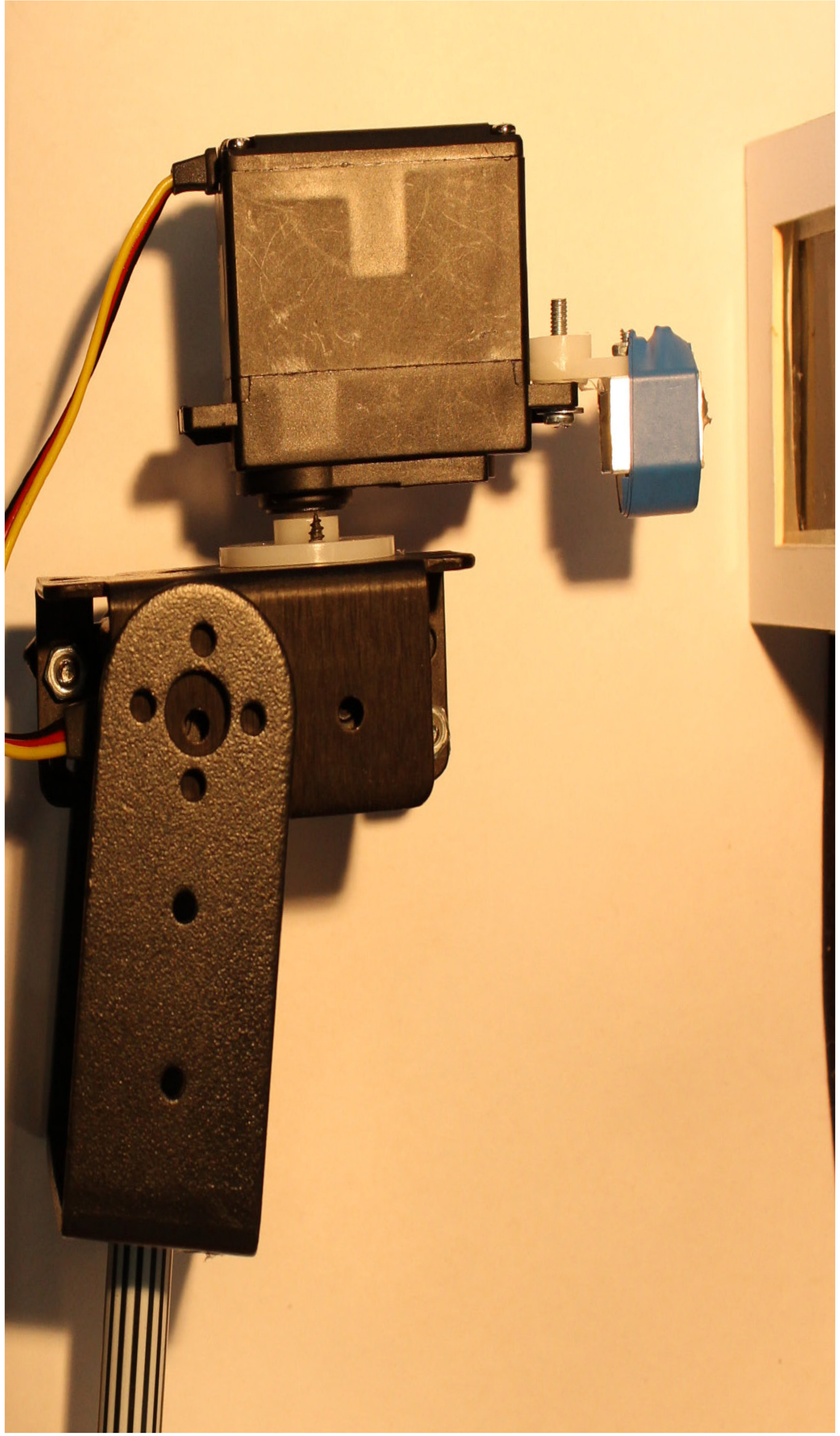




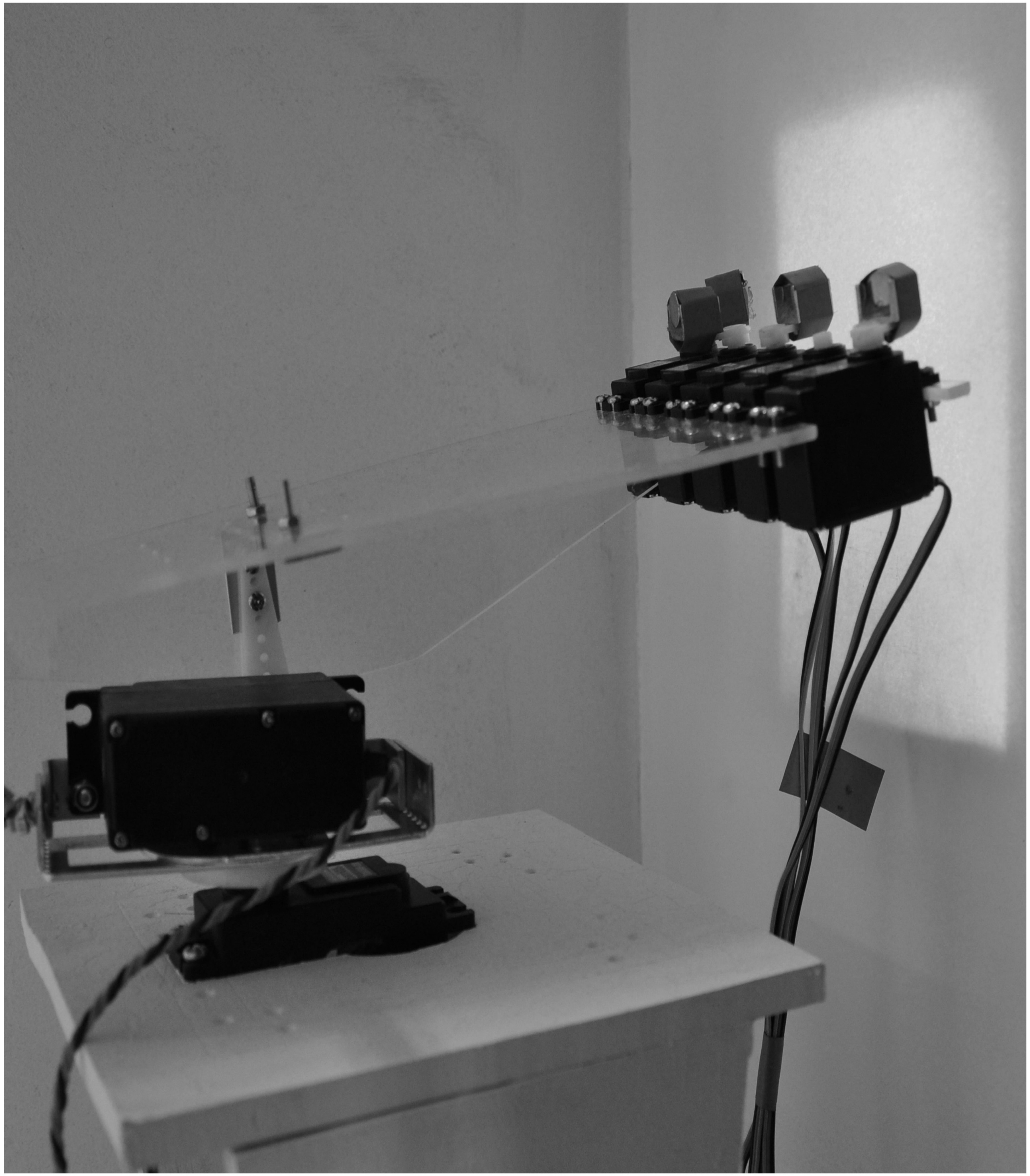


“Flying Fluid” Project

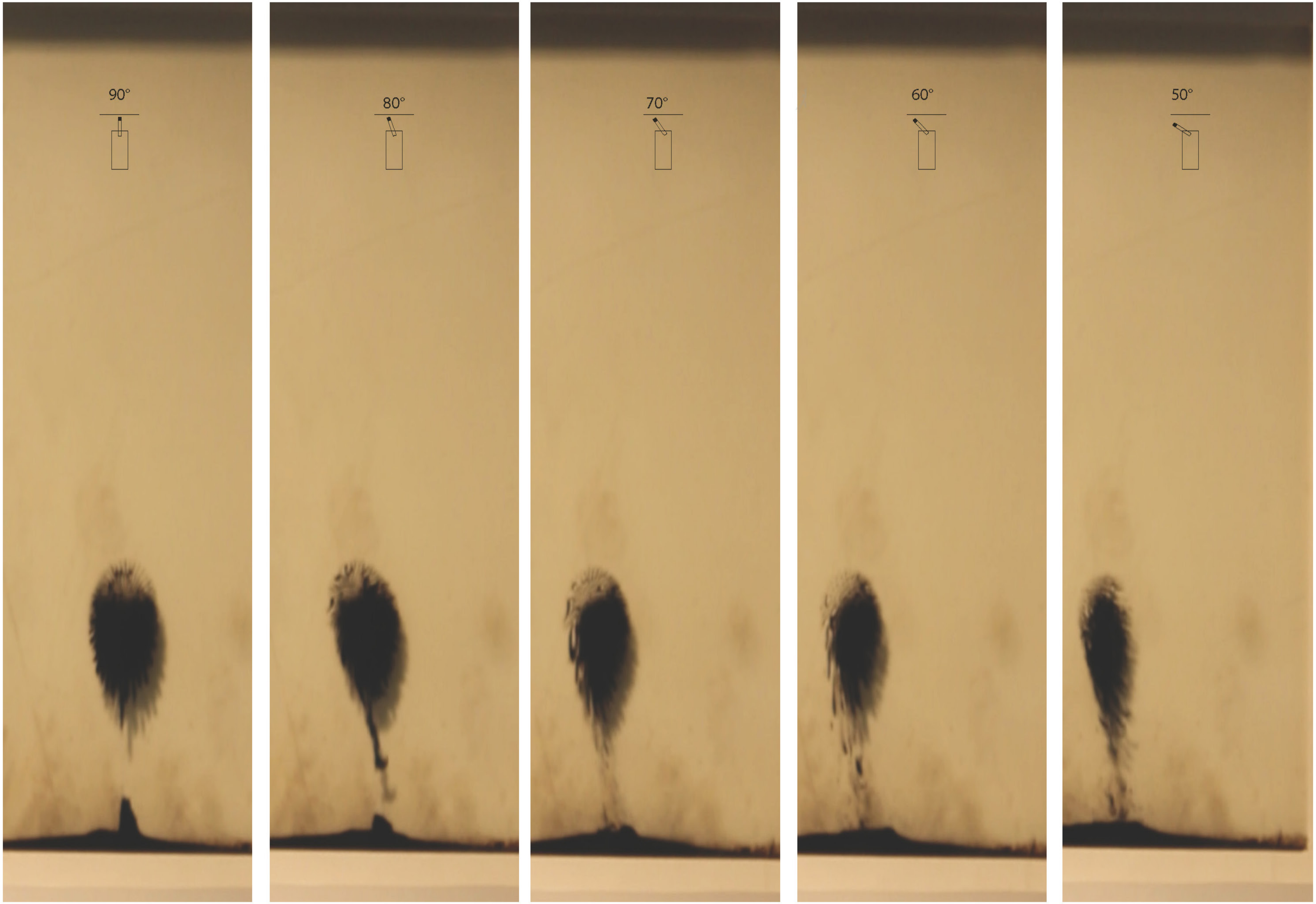
MANIPULATION OF FERROFLUID



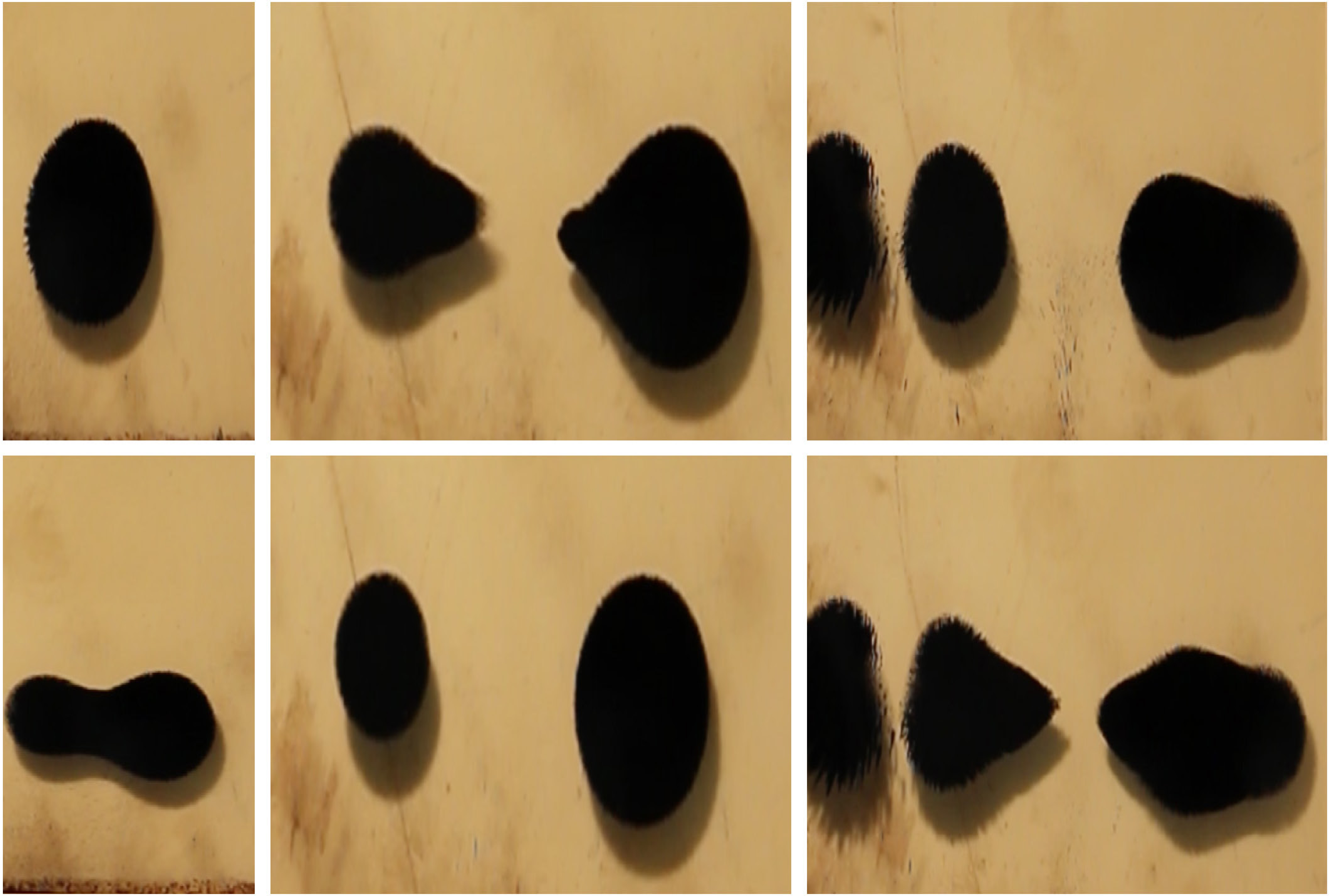
ROBOTIC MANIPULATION OF FERROFLUID IN FRAME



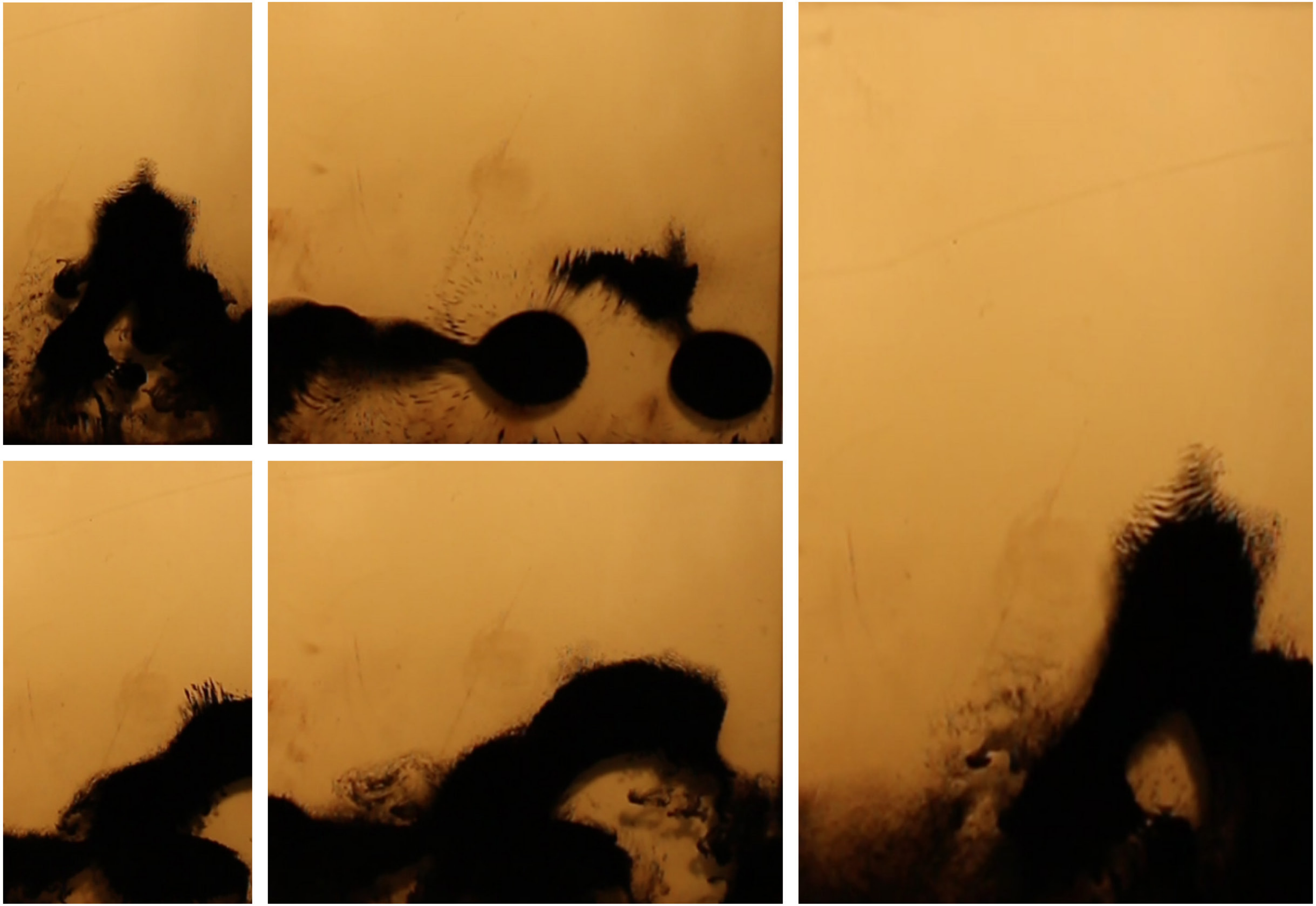
MANIPULATION OF FERROFLUID

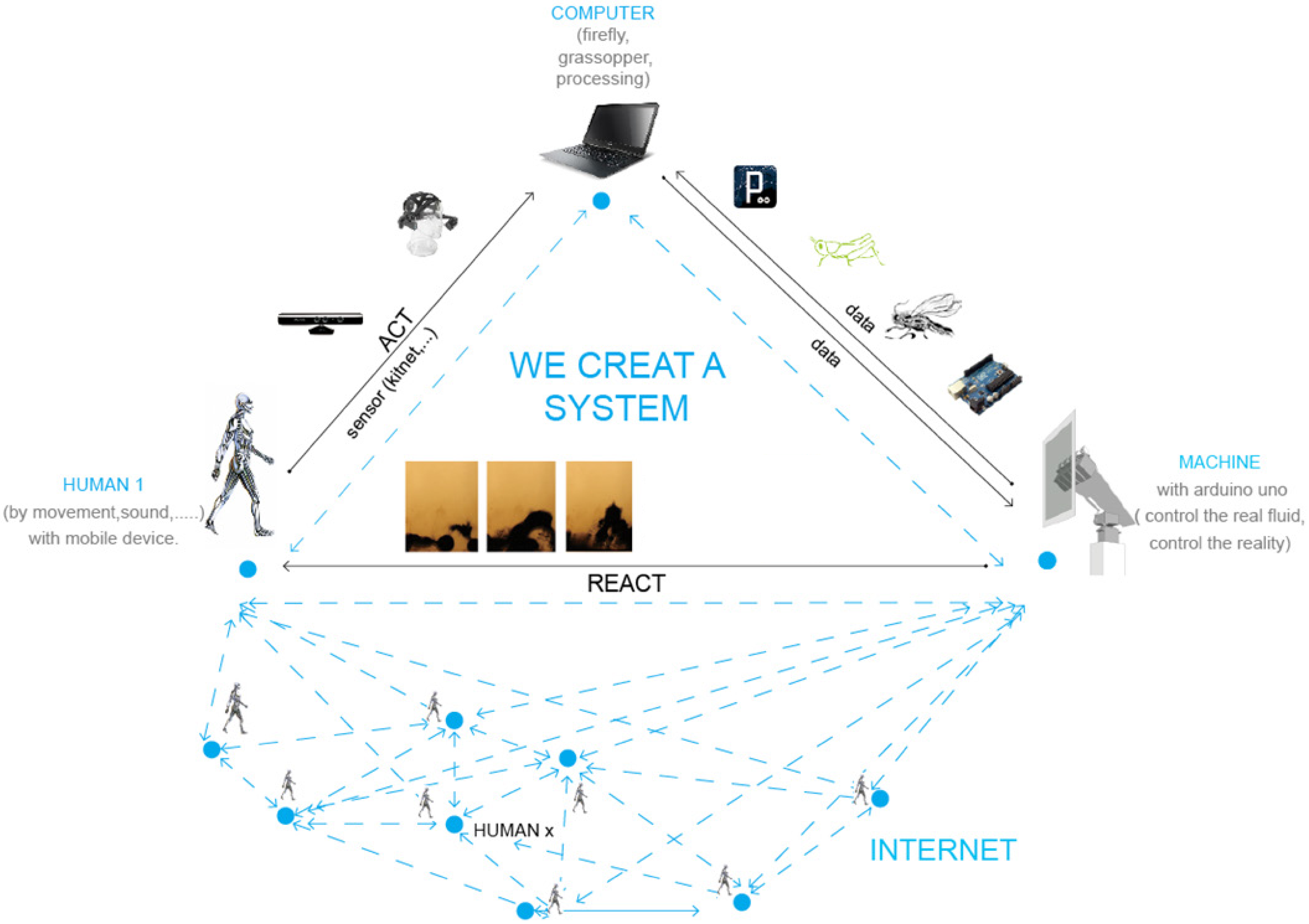


INTERFERENCE OF FERRO-FLUID IN MULTIPLE MAGNETIC FIELDS

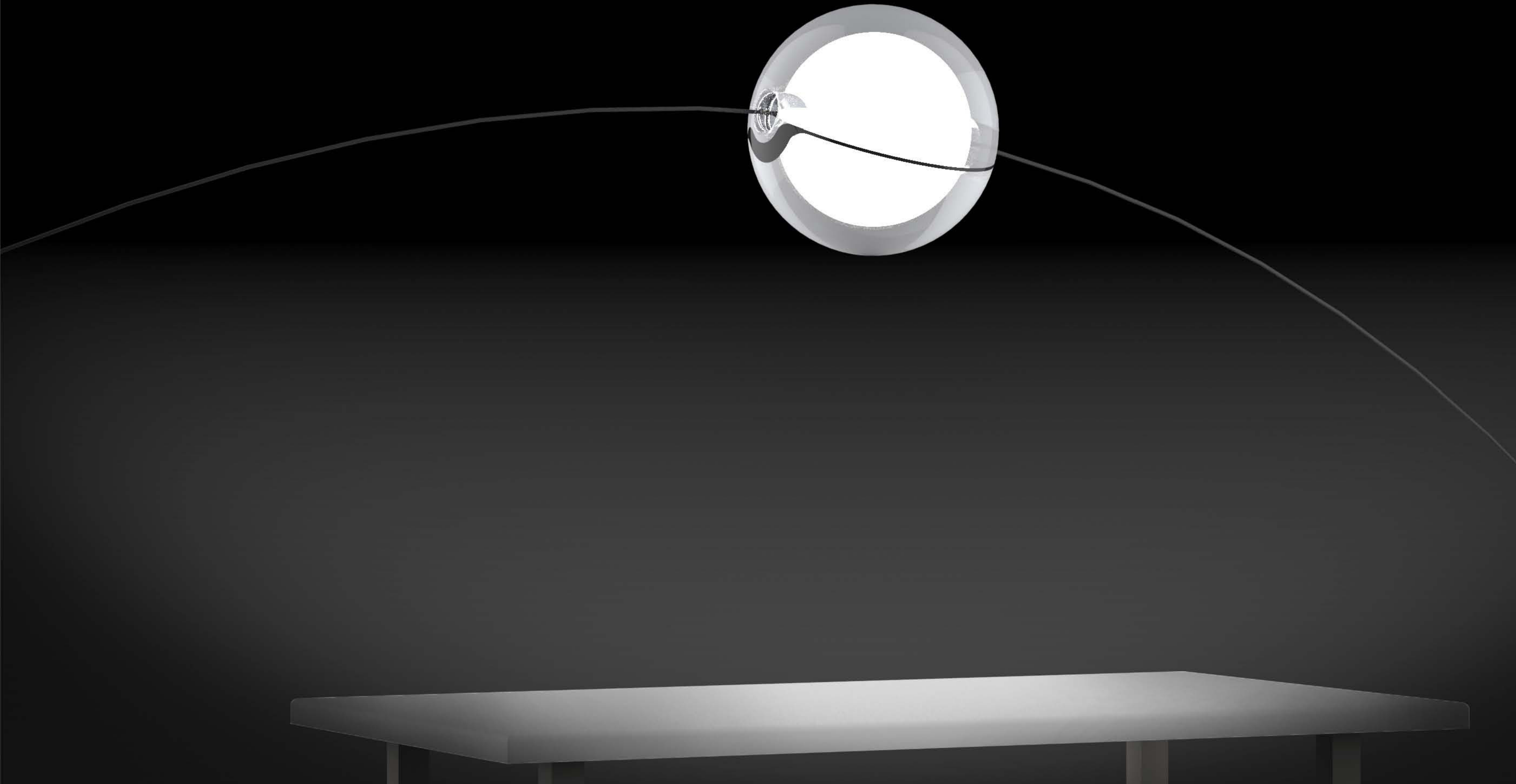


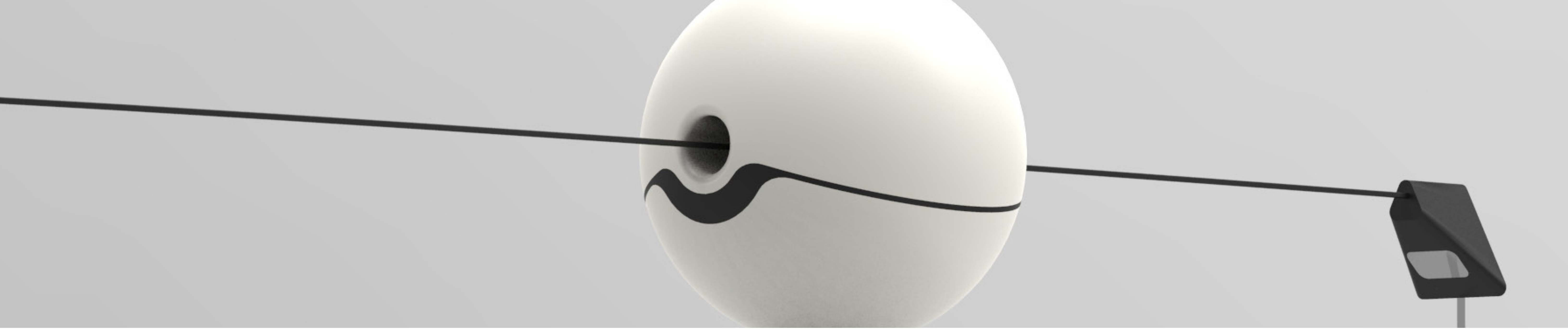
DESIGN AN ANIMATED DANCE

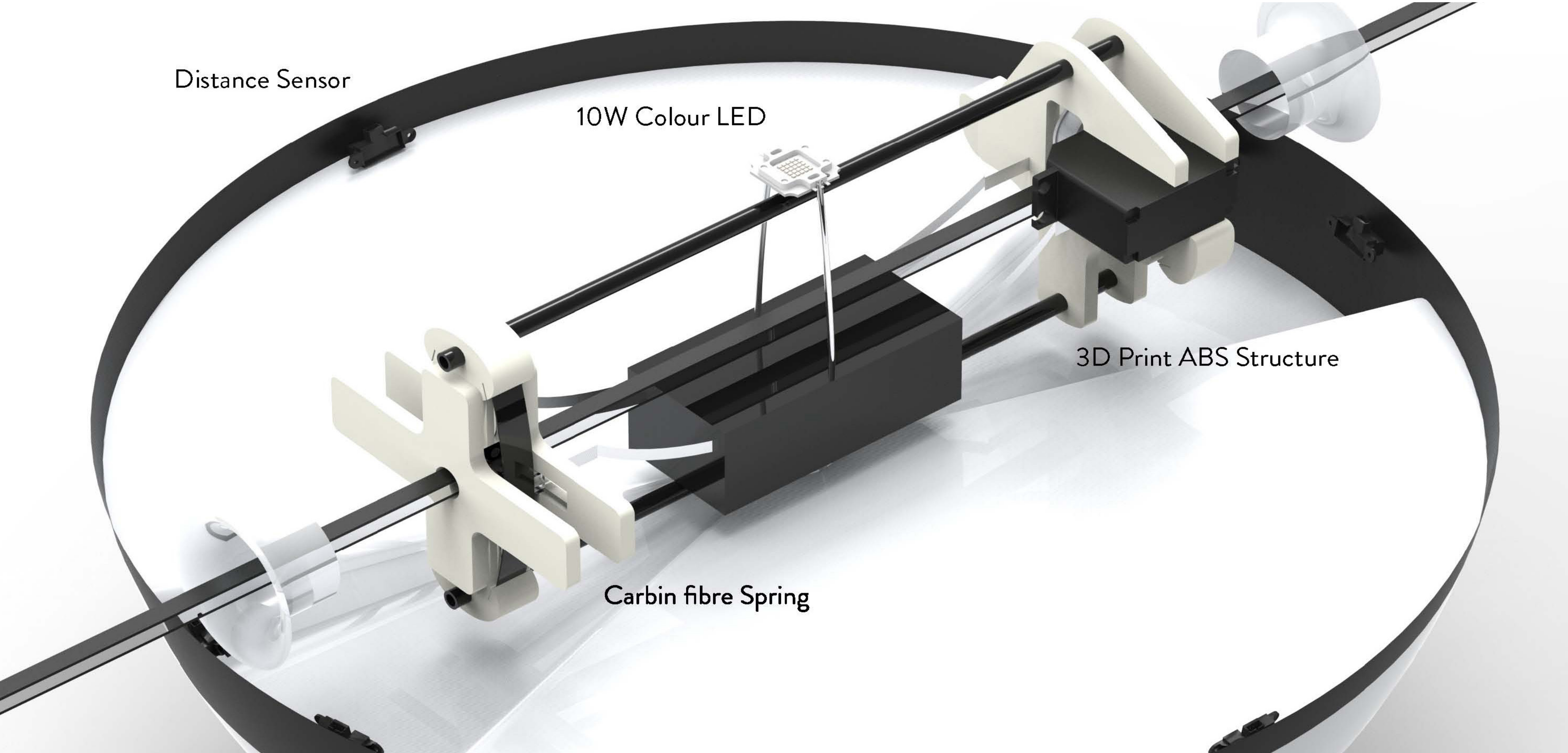


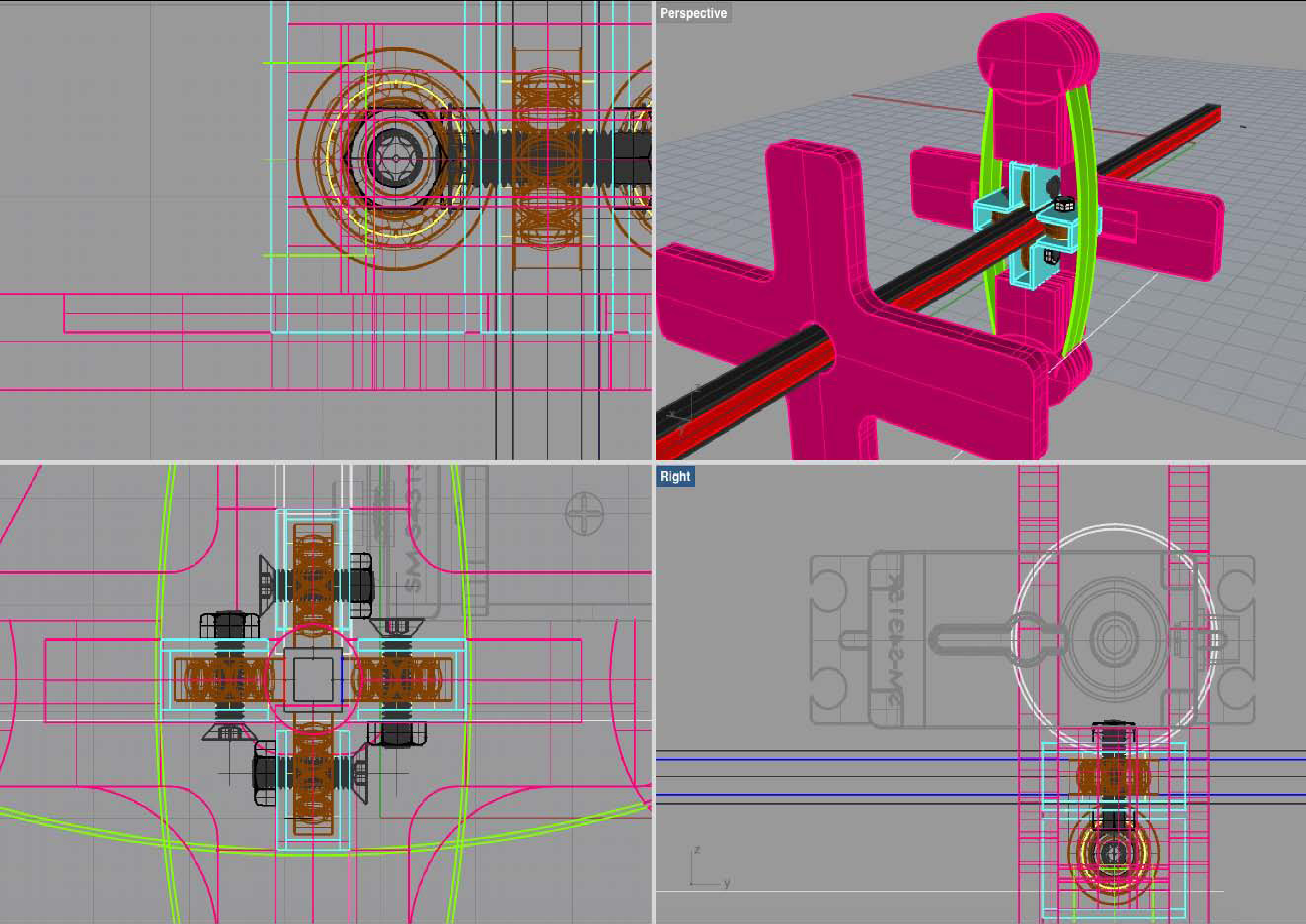

COMPUTER
(firefly,
grassopper,
processing)
ACT
sensor (kitnet,...)
data
data
WE CREAT A
SYSTEM
HUMAN 1
(by movement,sound,.....)
with mobile device.
MACHINE
with arduino uno
(control the real fluid,
control the reality)
REACT
HUMAN x
INTERNET

“Vision Light” Project

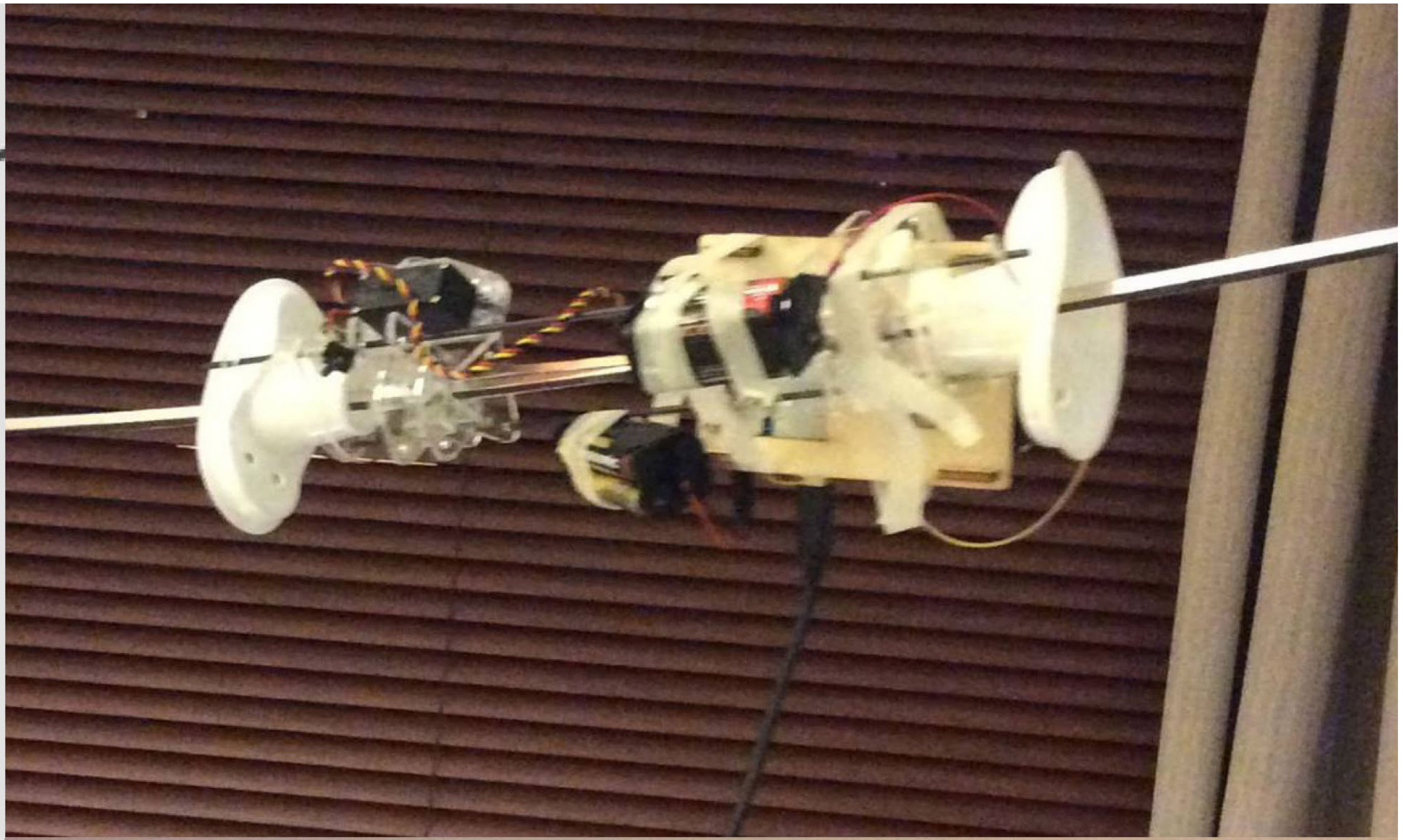


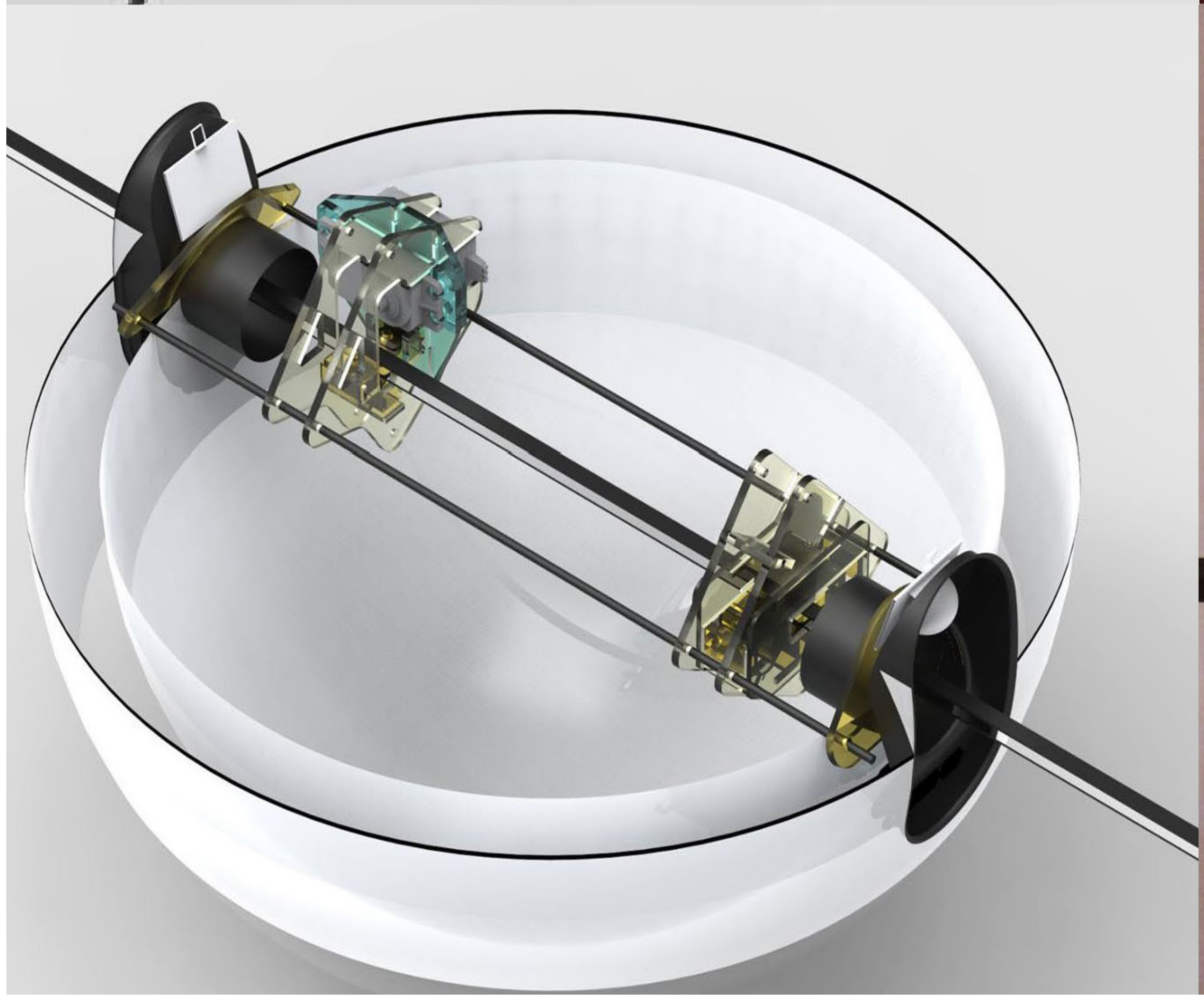


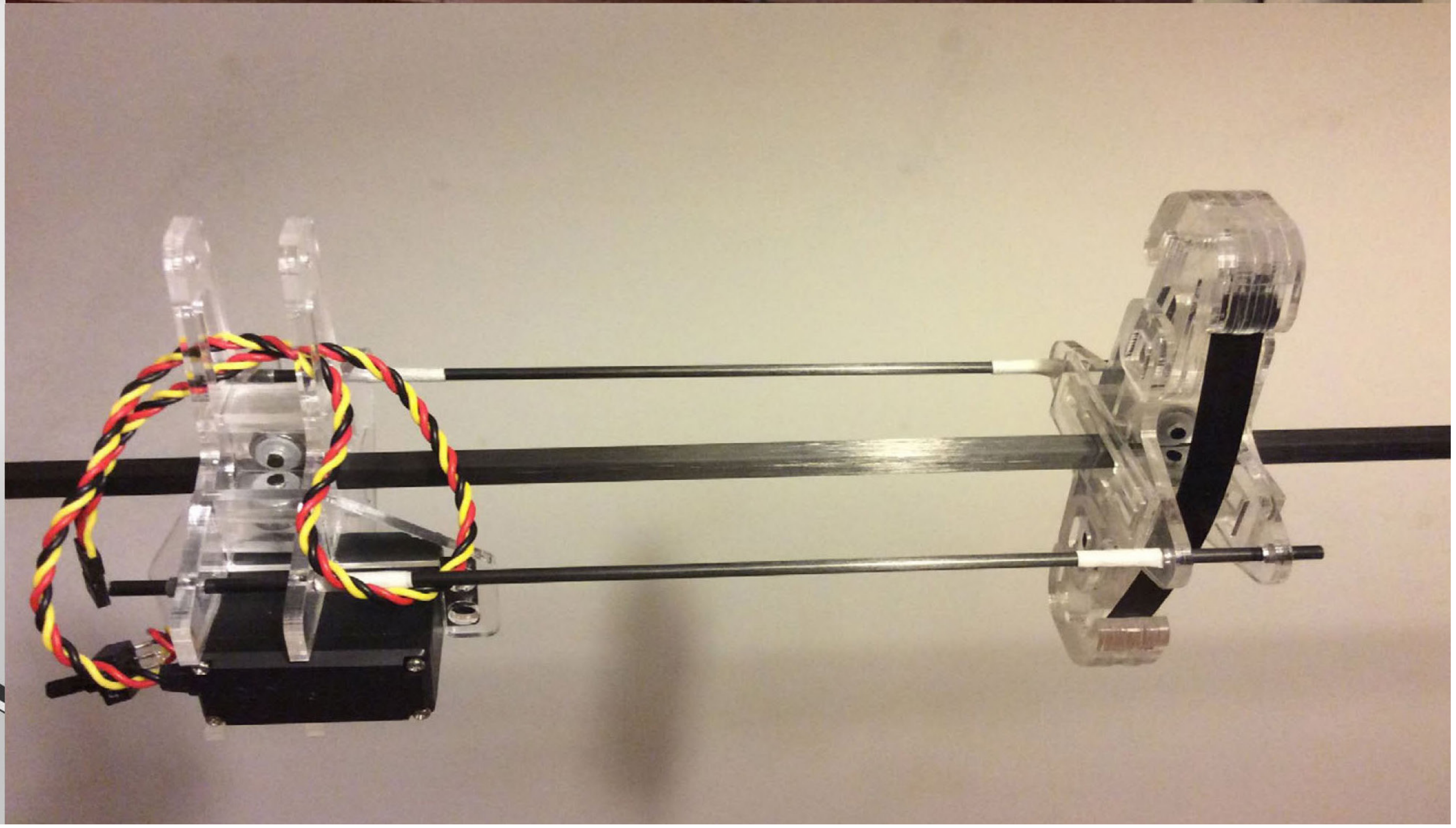

Distance Sensor
10W Colour LED
3D Print ABS Structure
Carbin fibre Spring


Perspective
Right
z
y

Vsion Light



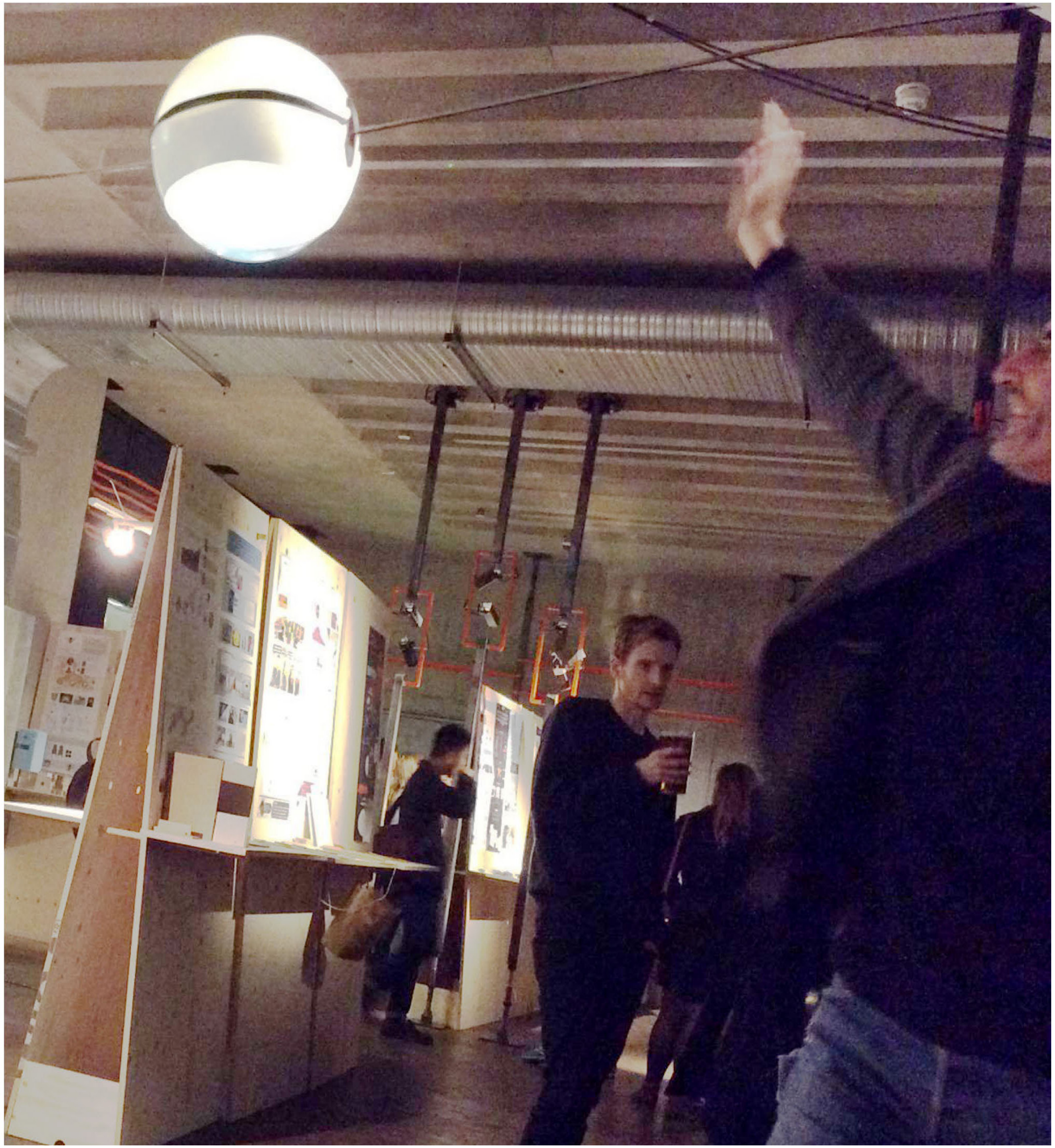




"Vision Light" Project (after graduate from Bartlett)

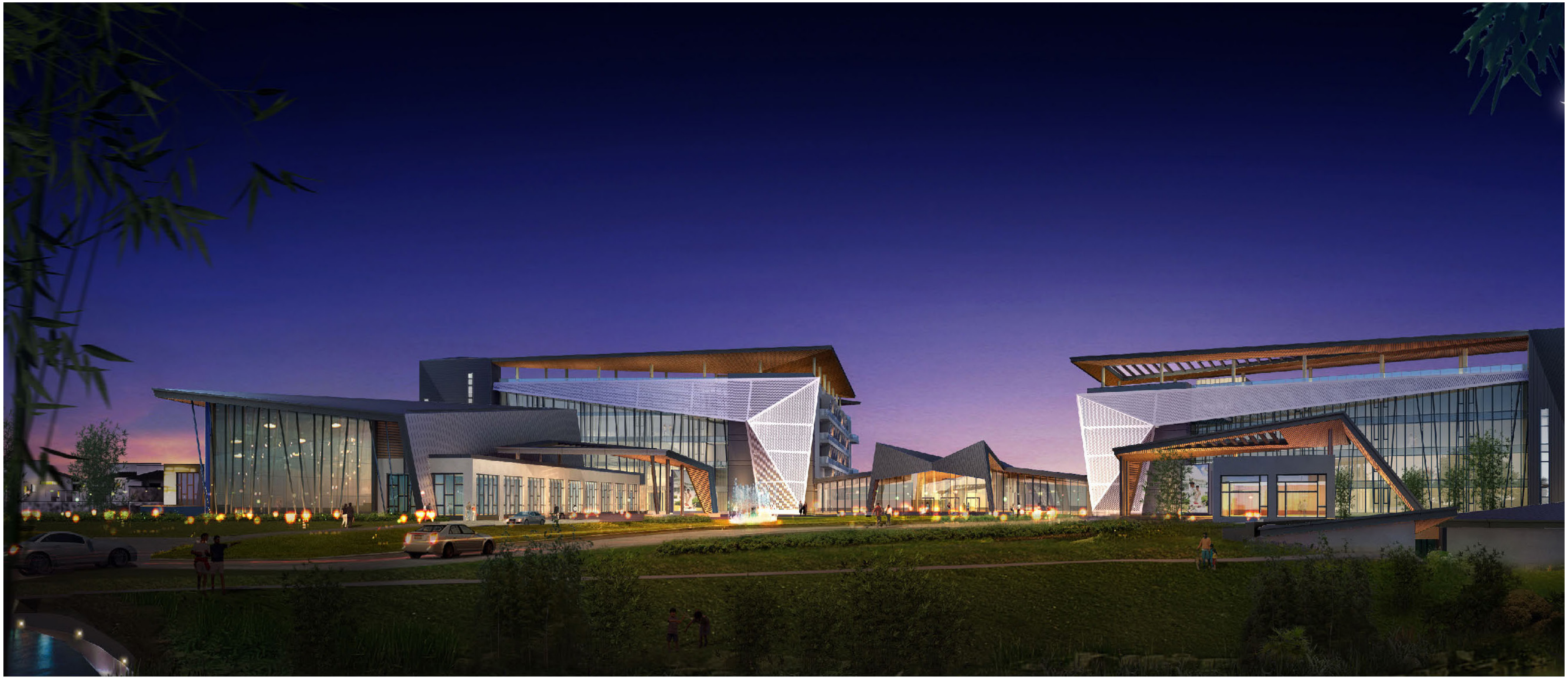
In this project(Working with Yu Harlan,I finished the software, adruino based hardware , and the kinetic servo based mechanism inside).

It is a round kinetic light which can moving towards you by detect your position and movement automatically. So it becomes an assistant but not only a tool for you. It was exhibited in UAL in Dec 3. Everyone likes it.



Architecture Design

Prospective rendering

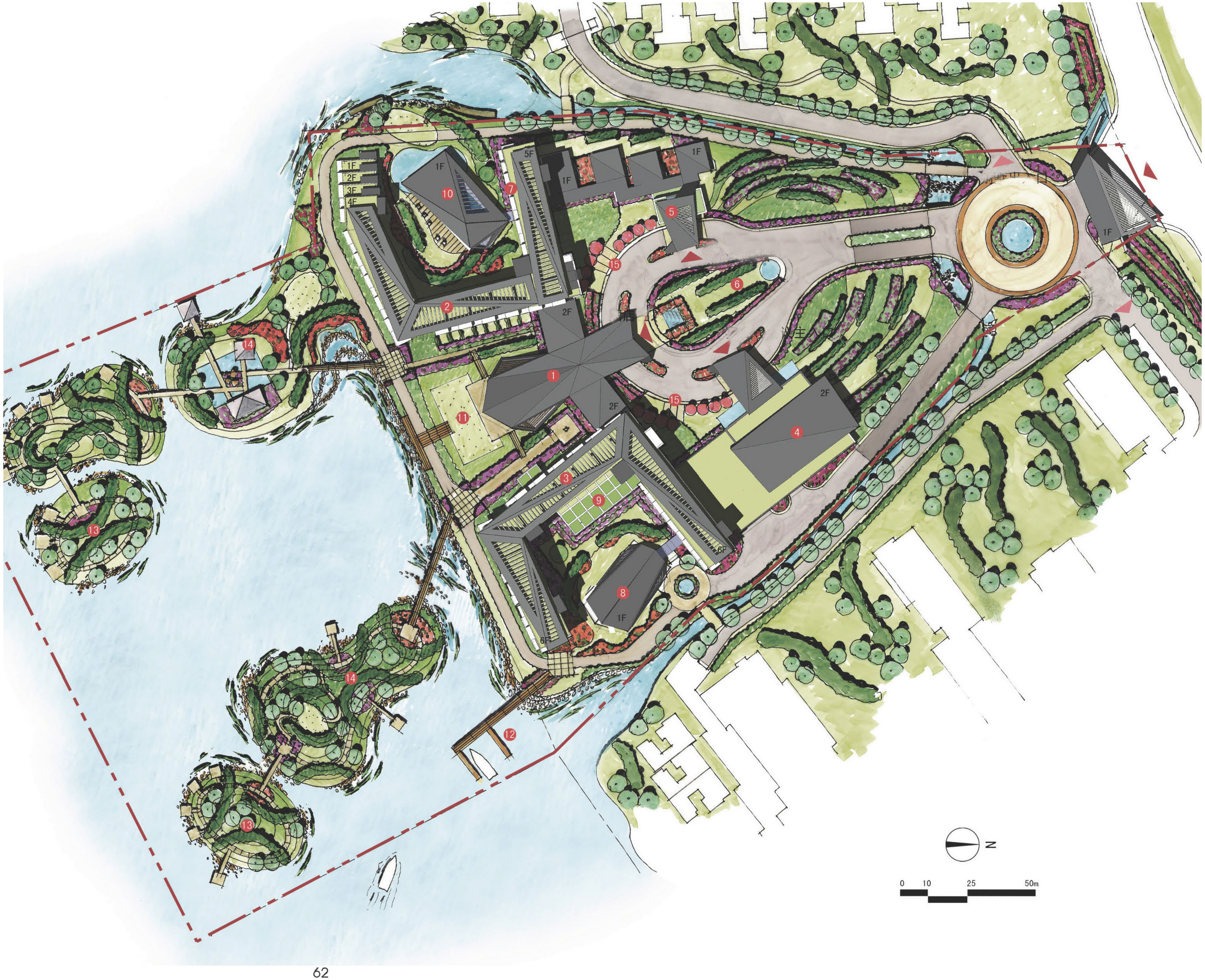


INTROUCTION

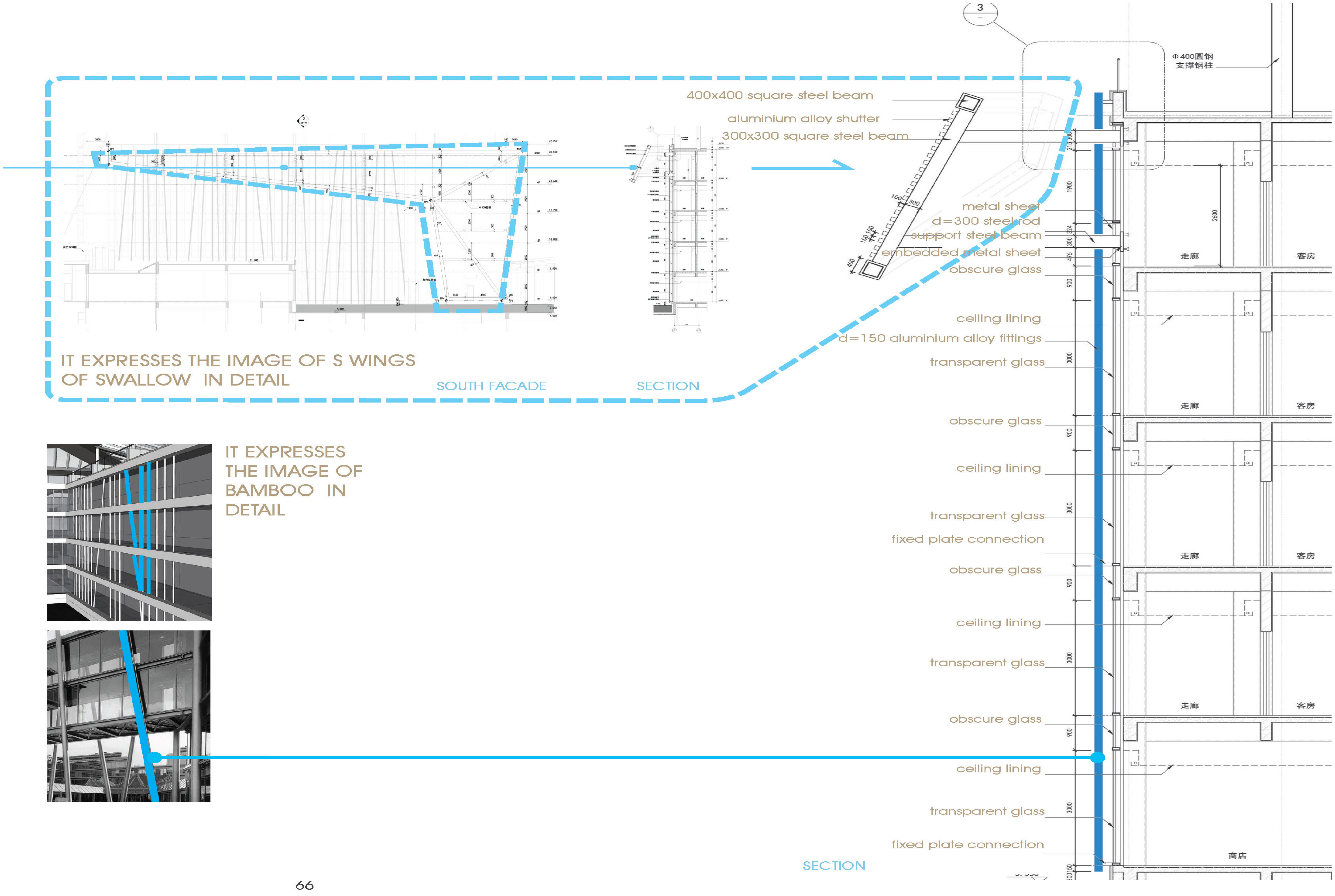
The building based in side of the famous scenic spot of suzhou taihu lake, and this project positioned as vacation type hotel, with single-family villas on the west and holiday apartment on the east. Clients are looking forward to build with fashionable Oriental flavor.

HangzhouTaihu Holiday Hotel

1 THE LOBBY
2 THE HOTEL
3 THE HOTEL
4 BANQUET HALL
5 SPA
6 FOUNTAIN
7 FITNESS CENTER
8 THE WEDDING
9 CATERING
10 SWIMMING POOL
11 LANDSCAPE GREENING
12 WHARF
13 WETLAND PARK
14 TEMPORARY HOTEL PARKING



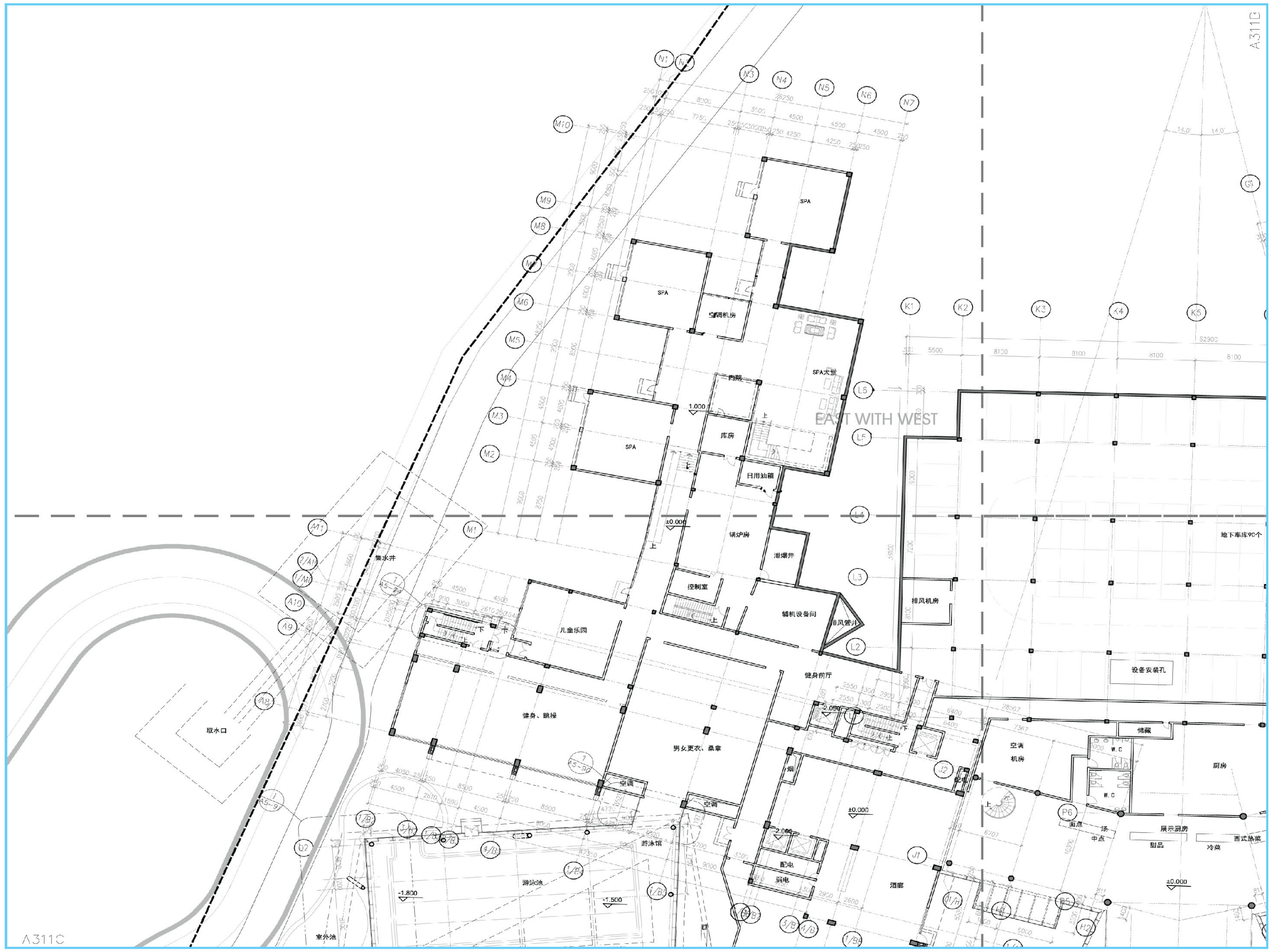
Detail design



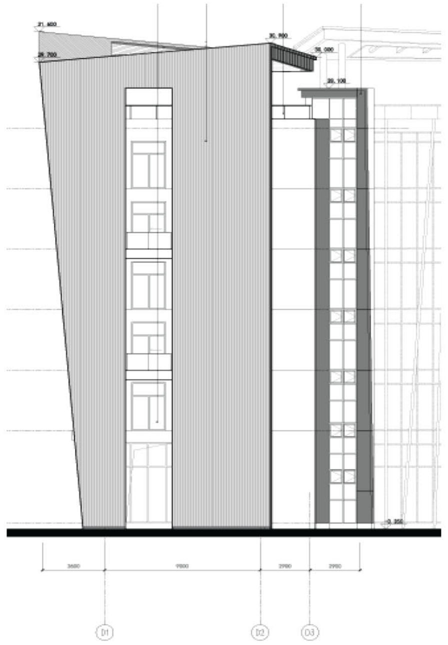
IT EXPRESSES THE IMAGE OF S WINGS OF SWALLOW IN DETAIL

IT EXPRESSES THE IMAGE OF BAMBOO IN DETAIL

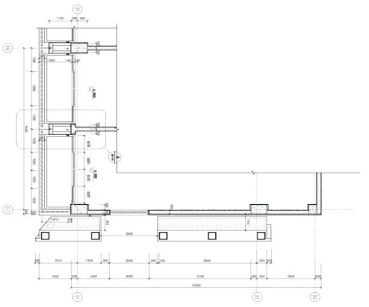
Plan and facade details



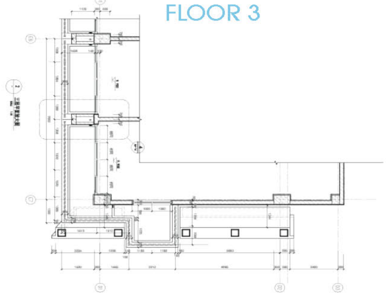
FLOOR 1



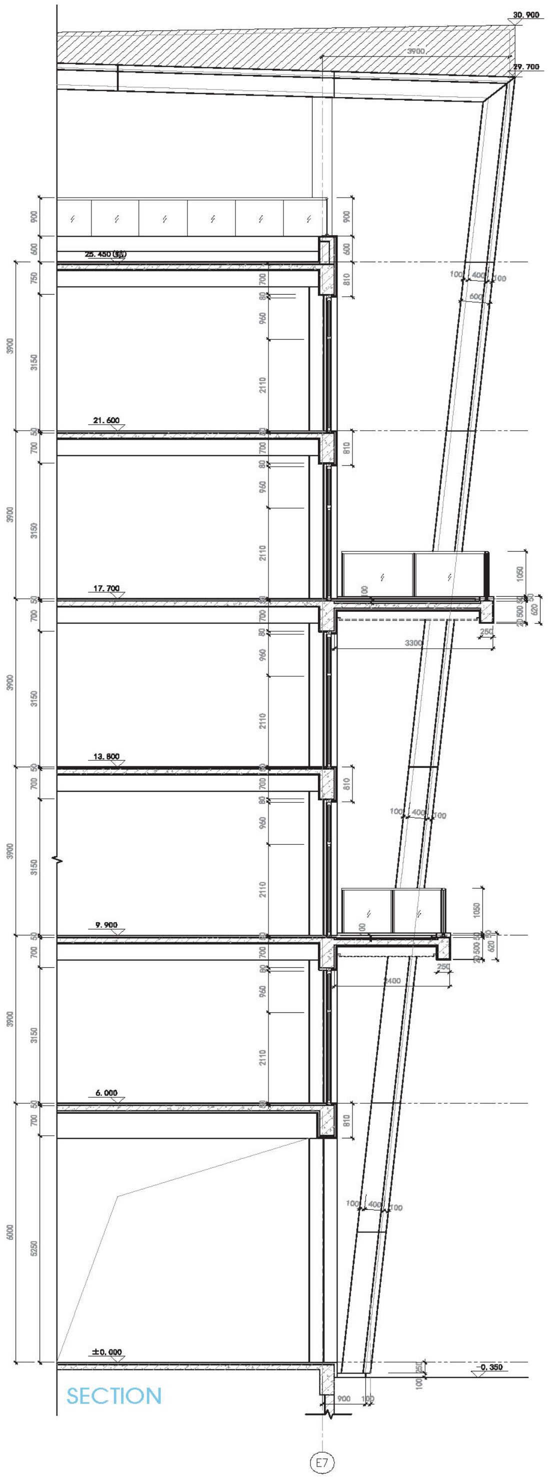
WEST FACADE



FLOOR 3

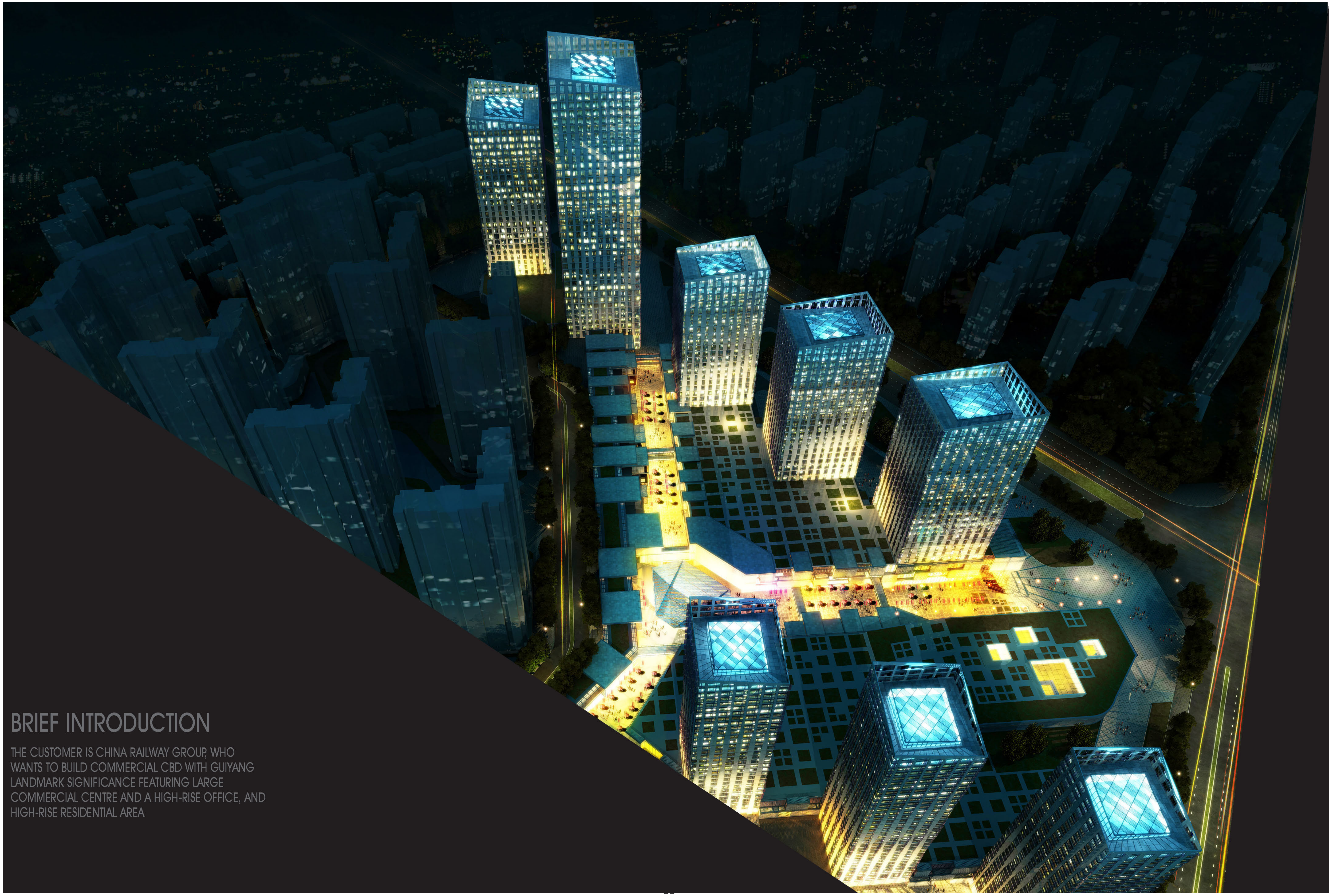


FLOOR 2



SECTION

Guiyang China Railway Center Project



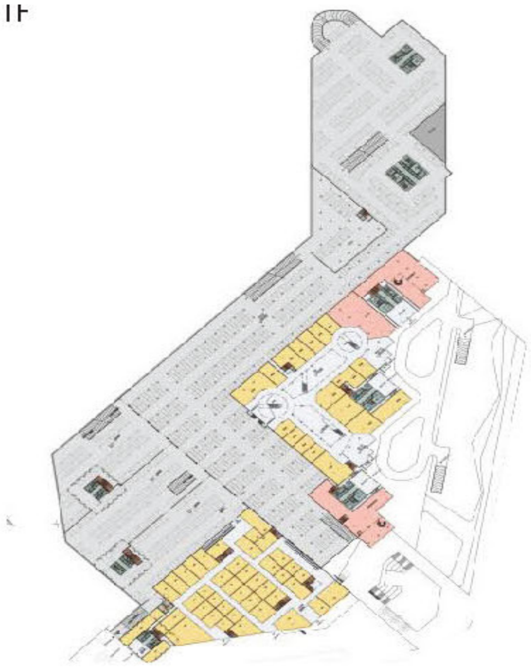
BRIEF INTRODUCTION

THE CUSTOMER IS CHINA RAILWAY GROUP, WHO WANTS TO BUILD COMMERCIAL CBD WITH GUIYANG LANDMARK SIGNIFICANCE FEATURING LARGE COMMERCIAL CENTRE AND A HIGH-RISE OFFICE, AND HIGH-RISE RESIDENTIAL AREA

Plan

— FLAGSHIP STORE
— SHOPS
— VIDEO GAMES CENTER
— CINEMA
— CATERING
— UNDERGROUND PARKING

-1F



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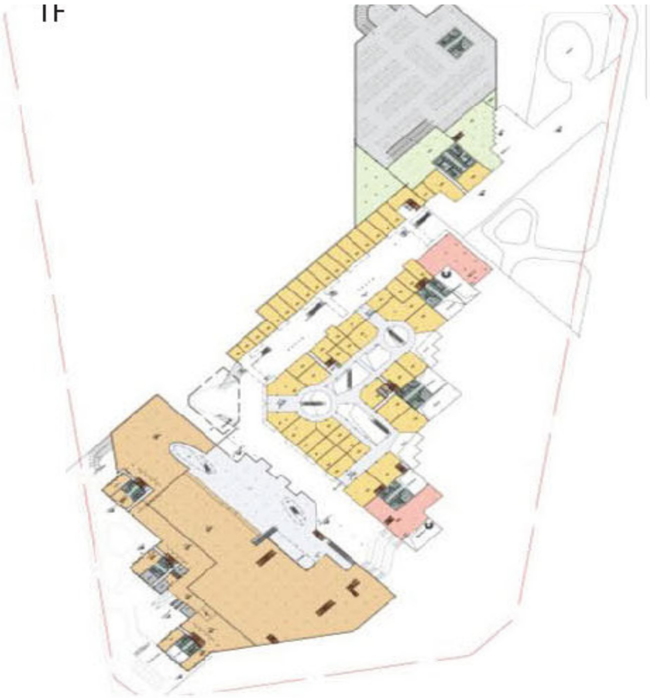

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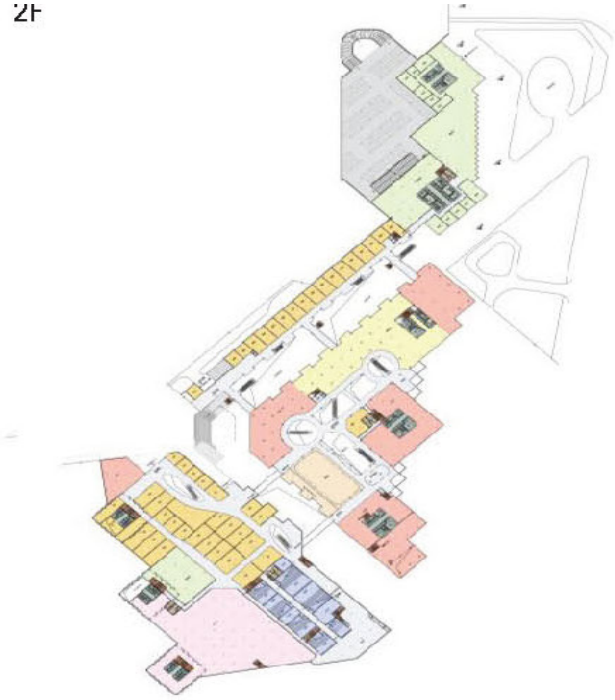

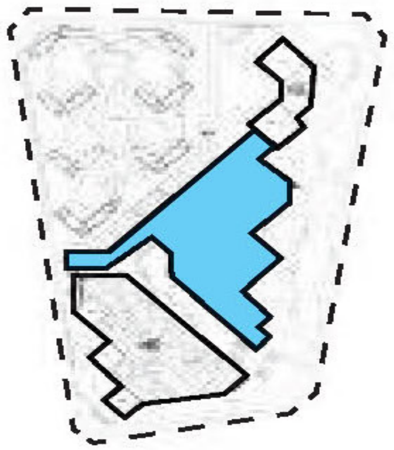

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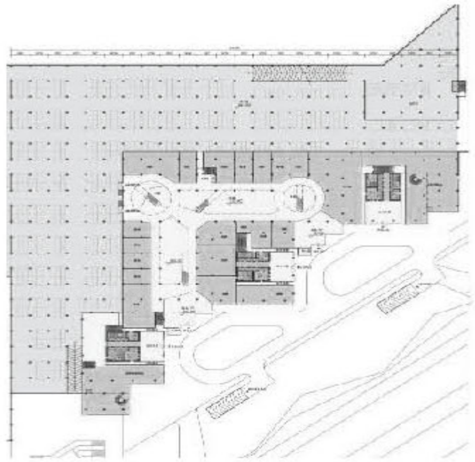

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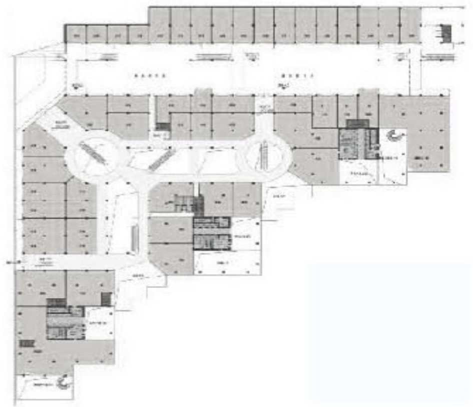

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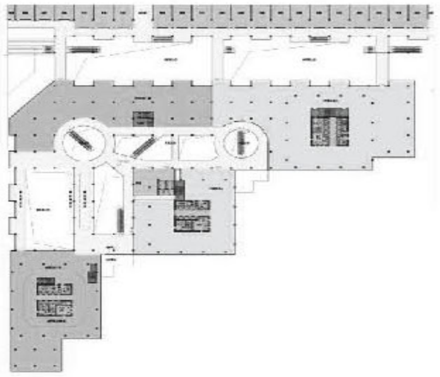

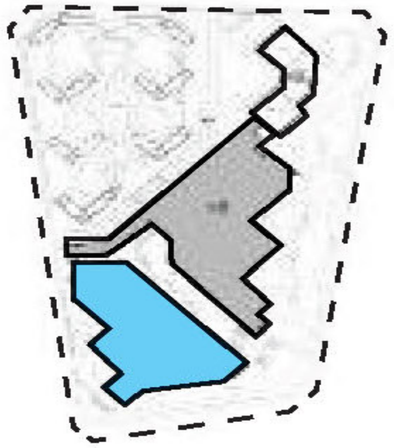

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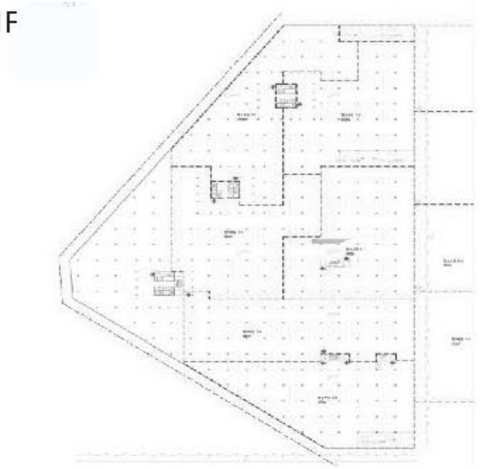

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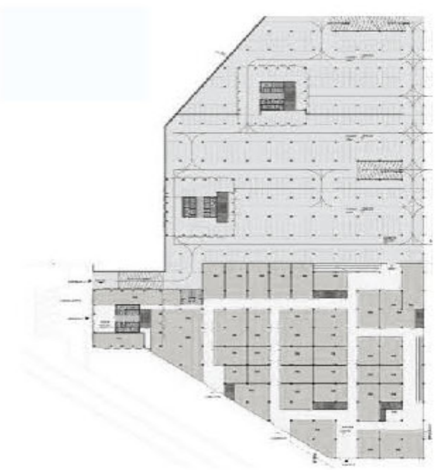

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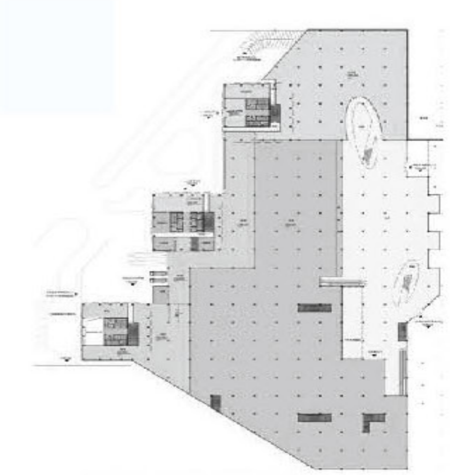
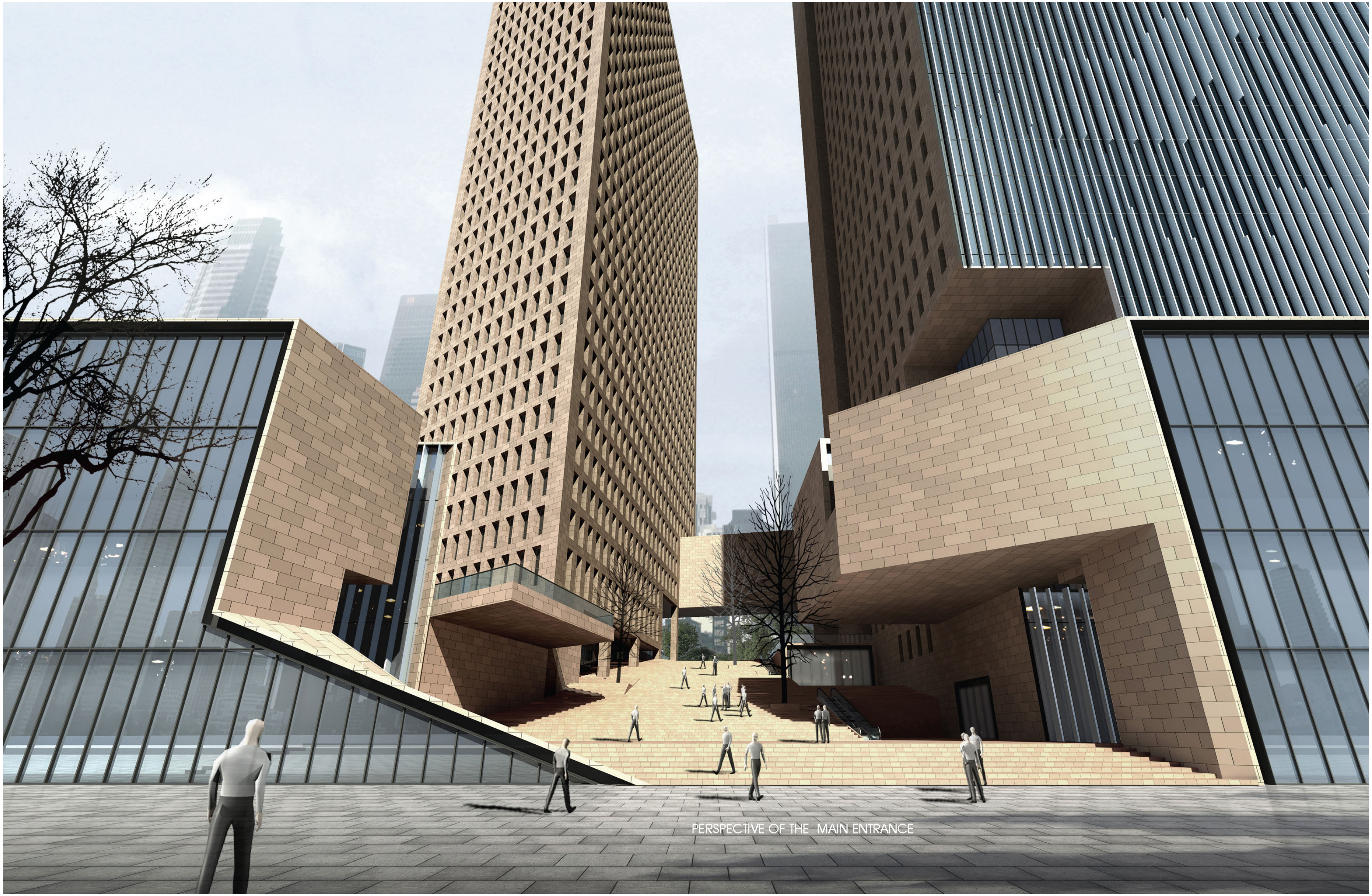


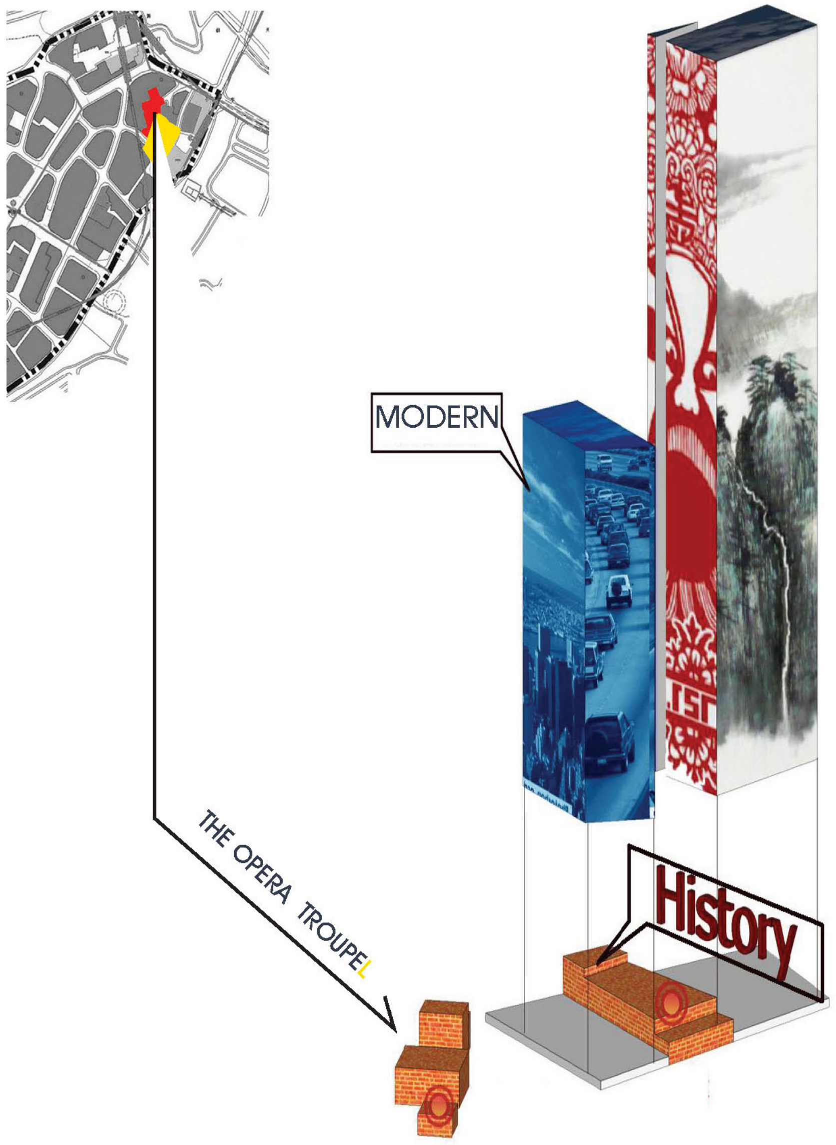
Super High Building for Opera

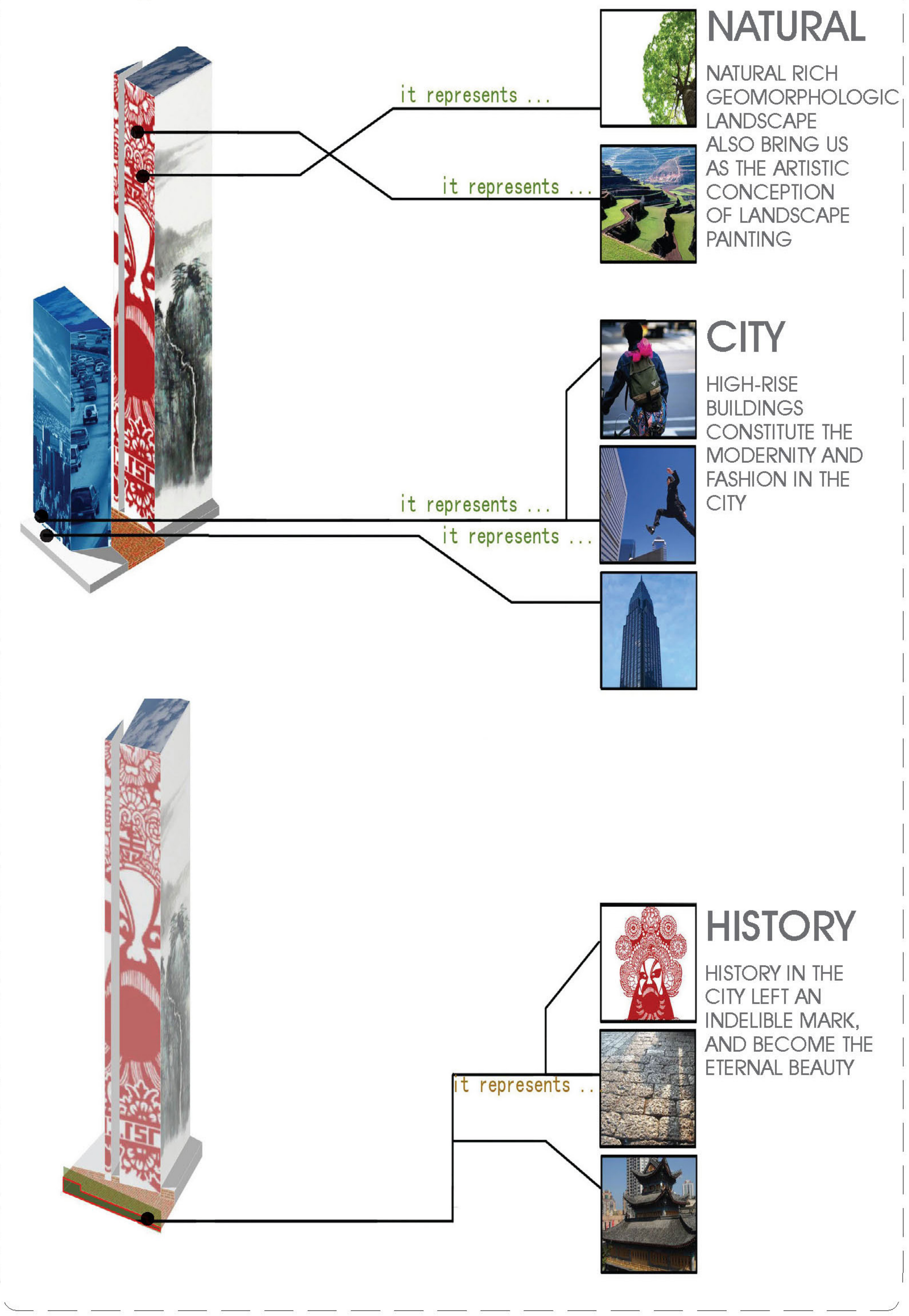


PERSPECTIVE OF THE MAIN ENTRANCE

Facadw design

IOHAN TEMPLE,
EIJING OPERA
ROUPE CLOSE THE
ROJECT, OUTER OF
IE CONSTRUCTION
IOULD
OMMUNICATE WITH
EXPECTATING
STORICAL DIALOGUE.
ERE MODERNITY
ND TRADITION ALSO
OLLIDES.





NATURAL

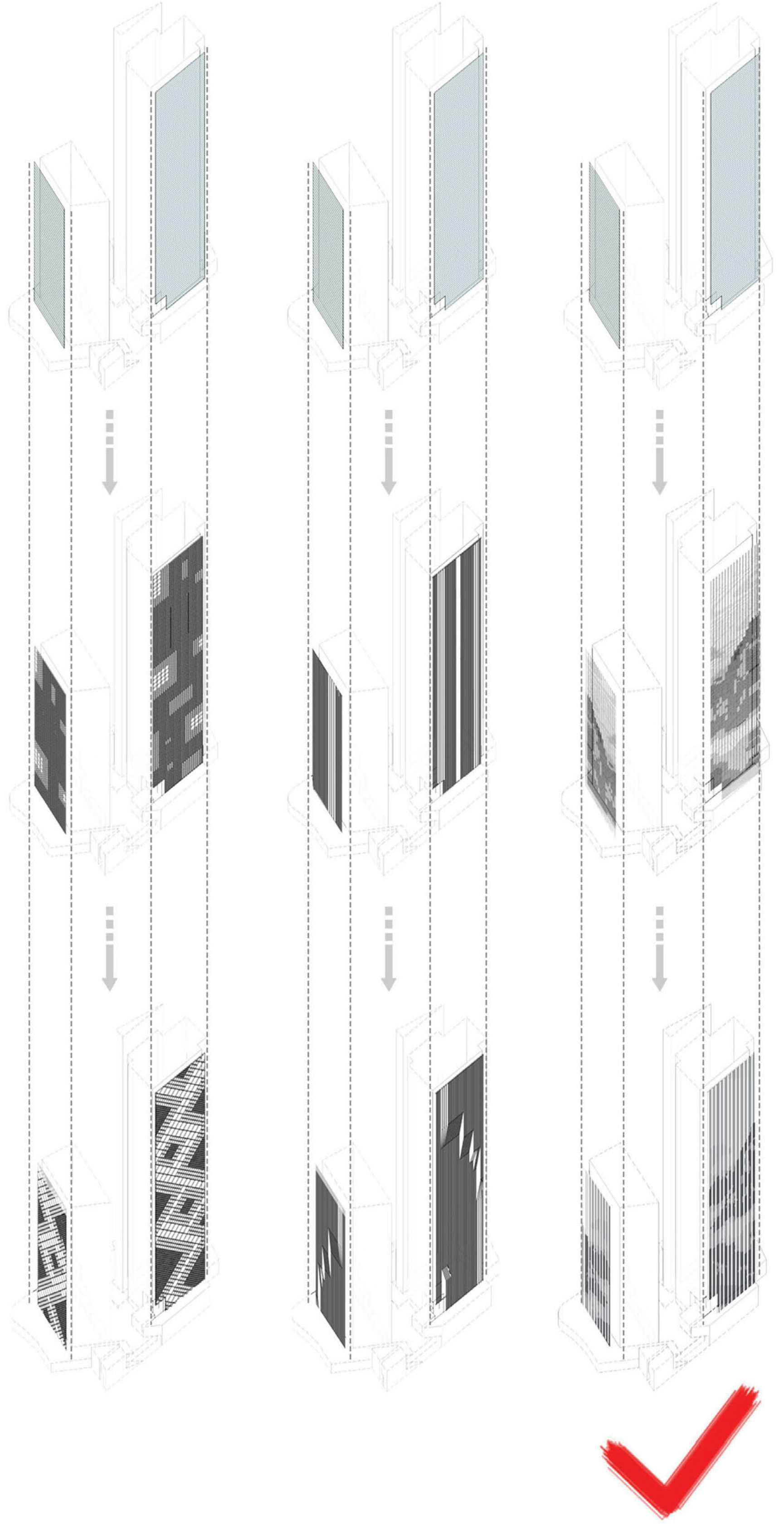
NATURAL RICH GEOMORPHOLOGIC LANDSCAPE ALSO BRING US AS THE ARTISTIC CONCEPTION OF LANDSCAPE PAINTING

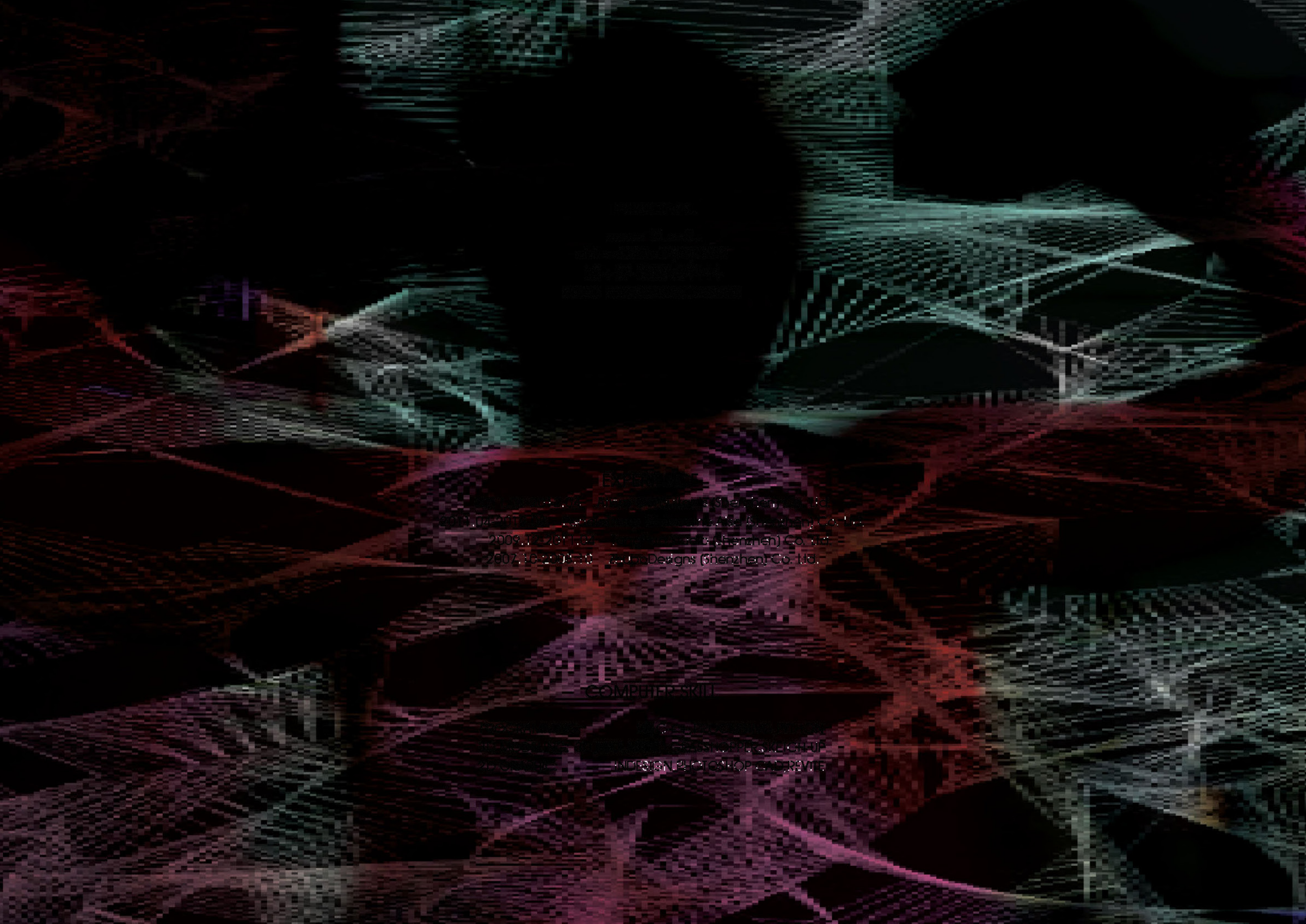
CITY

HIGH-RISE BUILDINGS CONSTITUTE THE MODERNITY AND FASHION IN THE CITY

HISTORY

HISTORY IN THE CITY LEFT AN INDELIBLE MARK, AND BECOME THE ETERNAL BEAUTY





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EXPE[illegible]

[illegible] Al[illegible] (Shenzhen) Co. Ltd.
2011.04-2011.[illegible] [illegible] Asia (Shenzhen) Co. Ltd.
2009.12-2011.04 [illegible] (Shenzhen) Co. Ltd.
2007.10-2008.10 [illegible]Designs (Shenzhen) Co. Ltd.

COMPUTER SKILL

[illegible] [illegible]
3D [illegible] [illegible] GRASSHOPPER,SKETCH-UP
2D GRAPHIC INDESIGN,PHOTOSHOP,CAD,REVITE